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Collier

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(54) **SYSTEM AND METHOD OF USE OF GYROSCOPIC FORCES ON ANIMAL EQUILIBRIUM**

(71) Applicant: **Greg Collier**, Lubbock, TX (US)
(72) Inventor: **Greg Collier**, Lubbock, TX (US)
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A01K 15/02 (2006.01)

(52) **U.S. Cl.**

CPC **A01K 15/02** (2013.01); **A01K 15/027** (2013.01)

(58) **Field of Classification Search**

CPC A01K 29/00; A01K 29/005; A01K 15/02; A01K 15/027; A61B 5/0002
USPC 54/71, 1; 74/5 R, 5.1, 5.12, 5.2, 5.22, 74/5.34, 5.37, 5.4, 5.47; 119/712, 815, 119/839, 850, 856-859, 174, 908, 905, 119/907; 434/225; 601/85, 112

See application file for complete search history.

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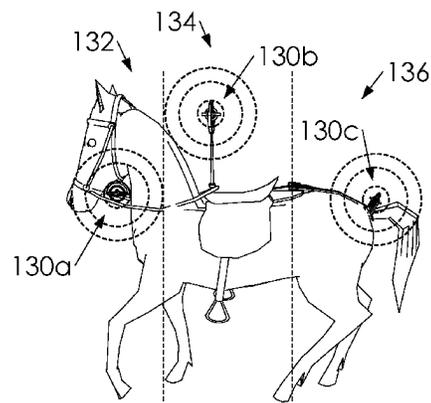
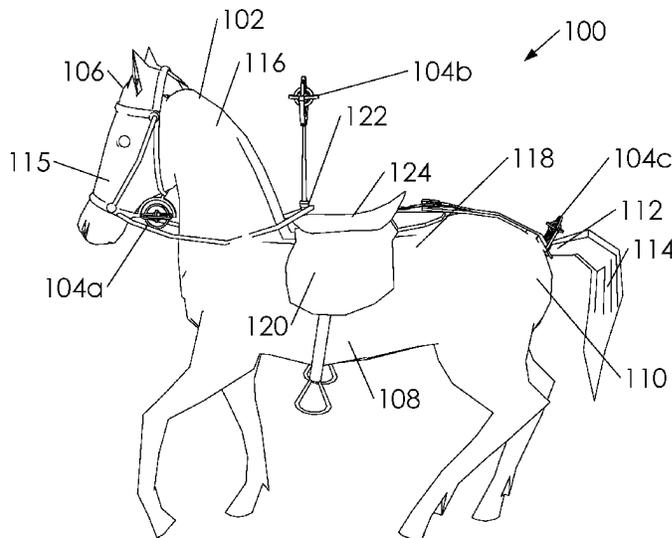
Primary Examiner — Joshua Huson

(74) Attorney, Agent, or Firm — Shannon L Warren

(57) **ABSTRACT**

An animal training system is disclosed. Said animal training system comprises a one or more gyrosopic assemblies each having a one or more rotors, a one or more gyroscope brackets, a power source attached to a one or more engines, and a one or more gyrosopic resistance forces. Said one or more rotors each comprise an axis. Said one or more gyroscope brackets attaching said one or more gyrosopic assemblies to an animal. Said one or more engines transmit a torque to said one or more rotors. Said one or more gyrosopic resistance forces are generated by rotating said one or more rotors in said one or more gyrosopic assemblies.

28 Claims, 31 Drawing Sheets



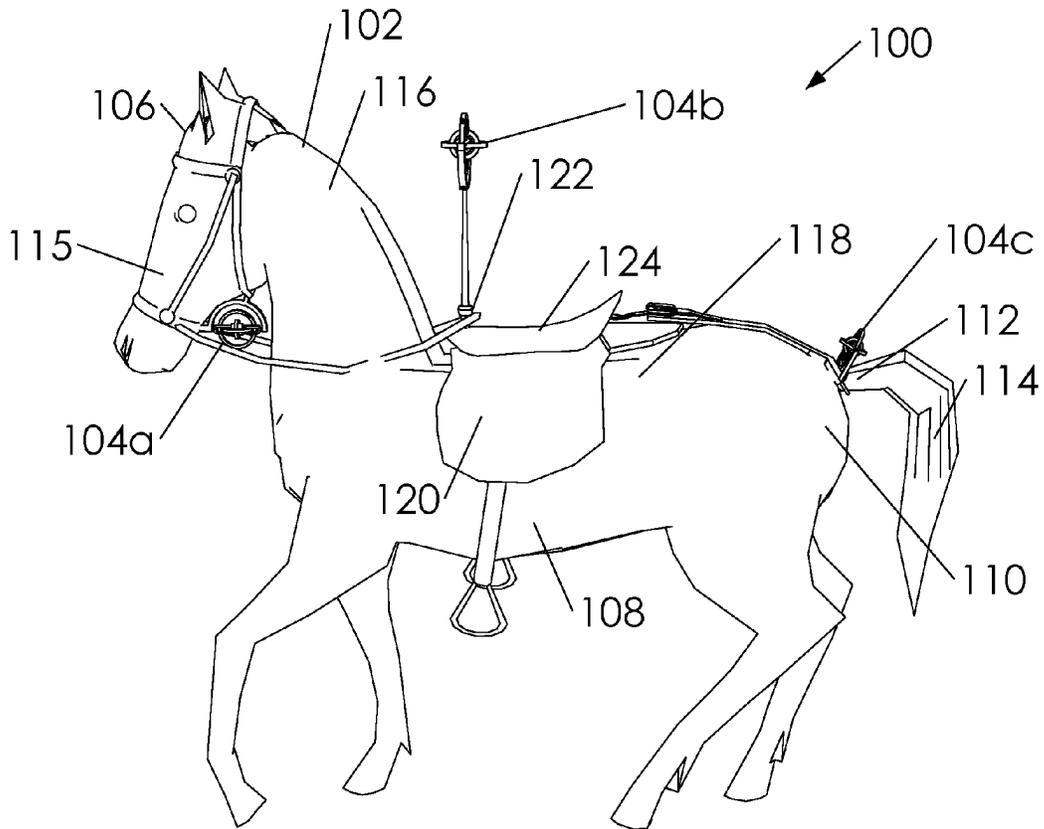


Fig. 1A

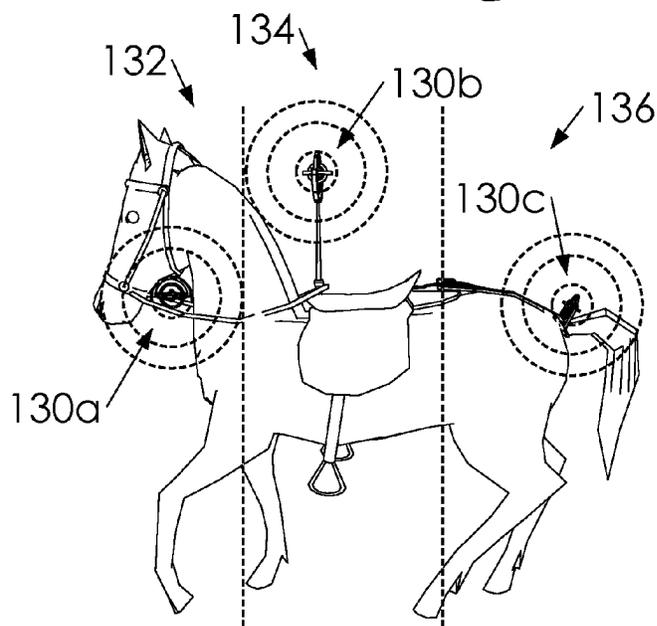
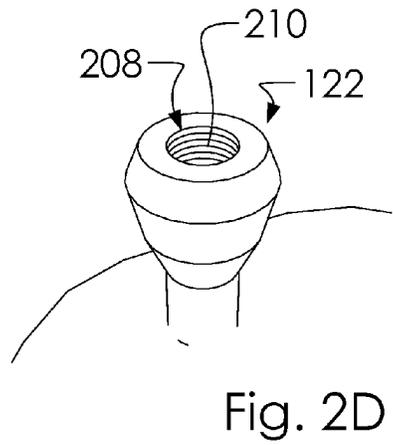
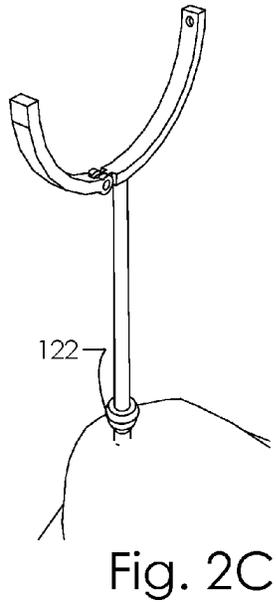
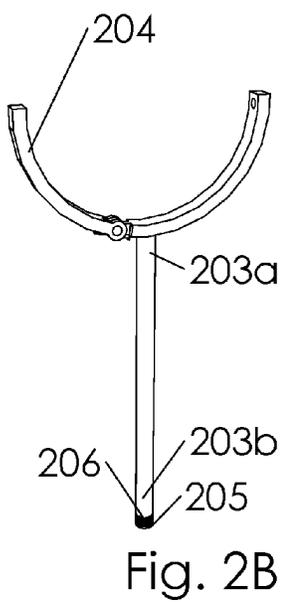
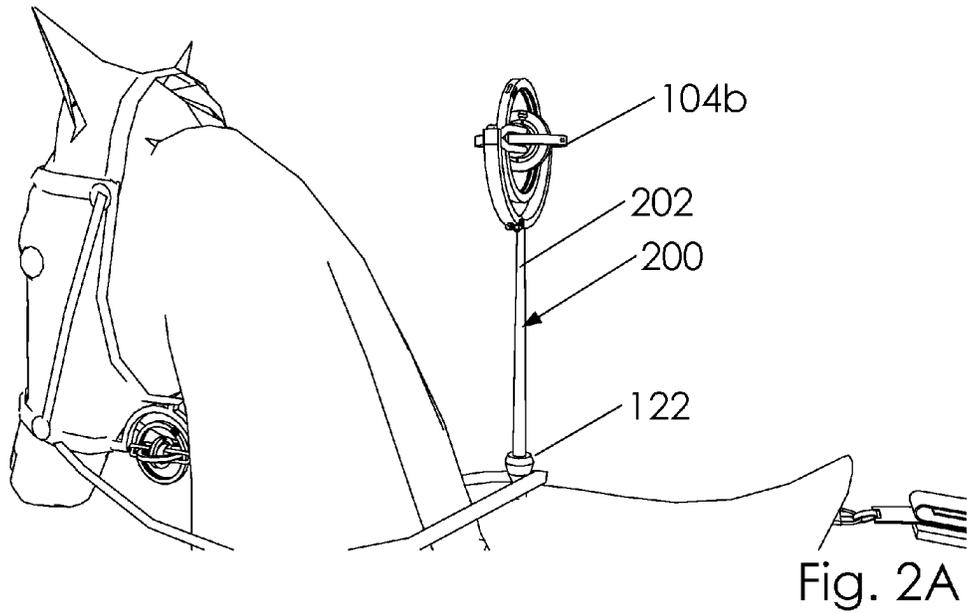


Fig. 1B



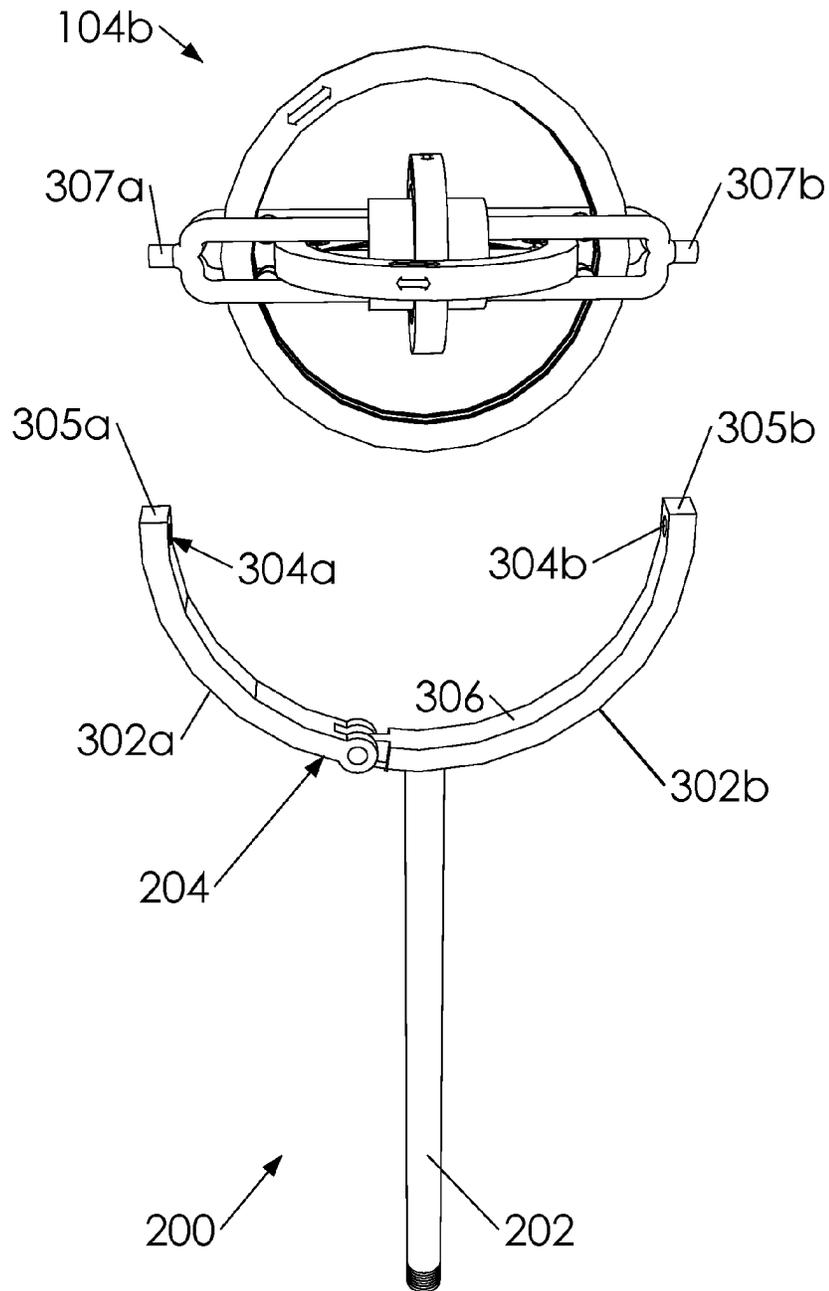


Fig. 3A

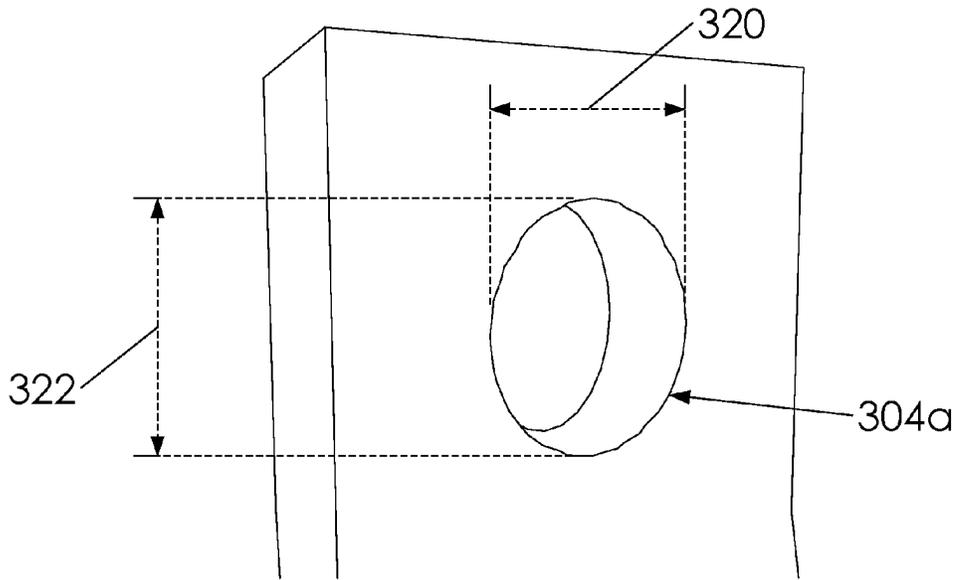


Fig. 3B

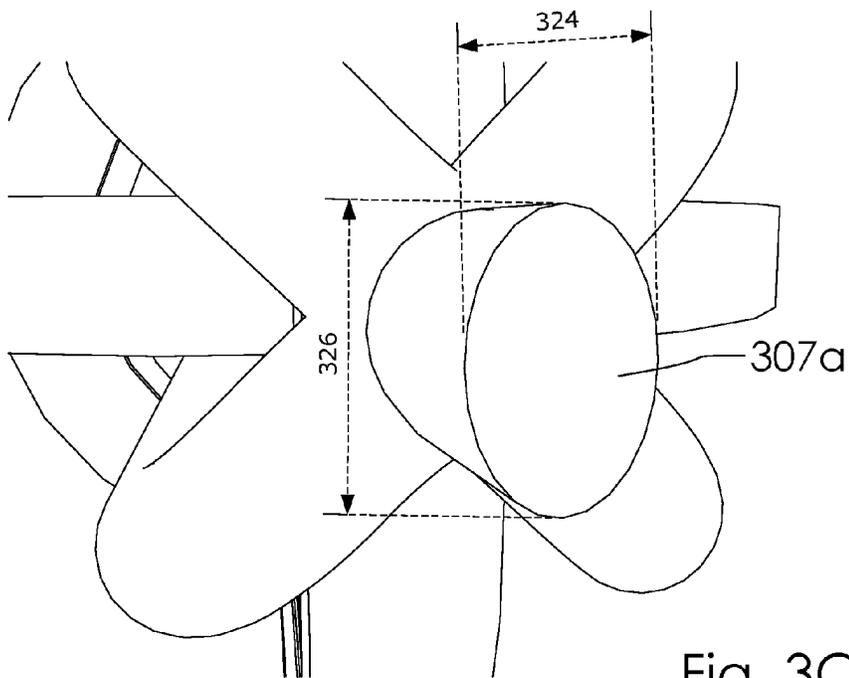


Fig. 3C

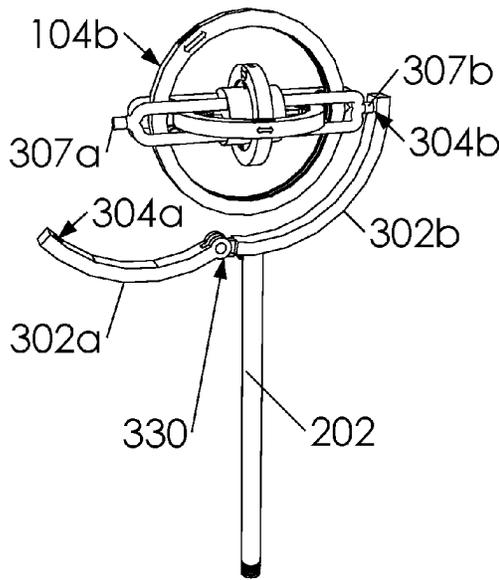


Fig. 3D

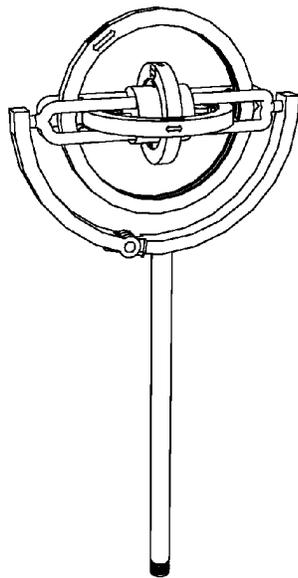


Fig. 3E

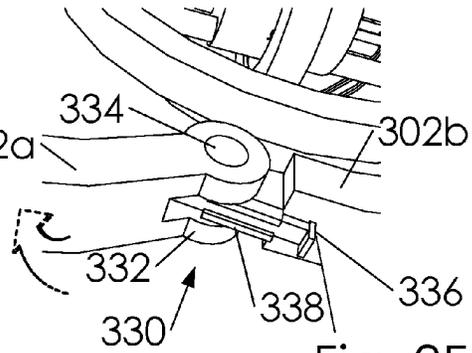


Fig. 3F

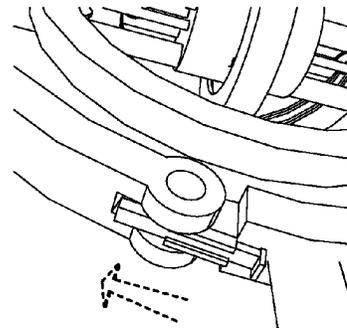


Fig. 3G

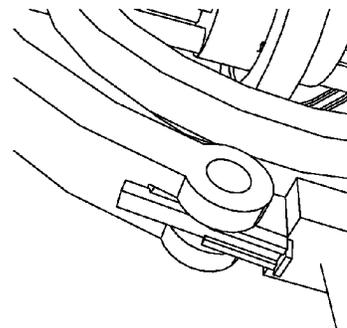


Fig. 3H

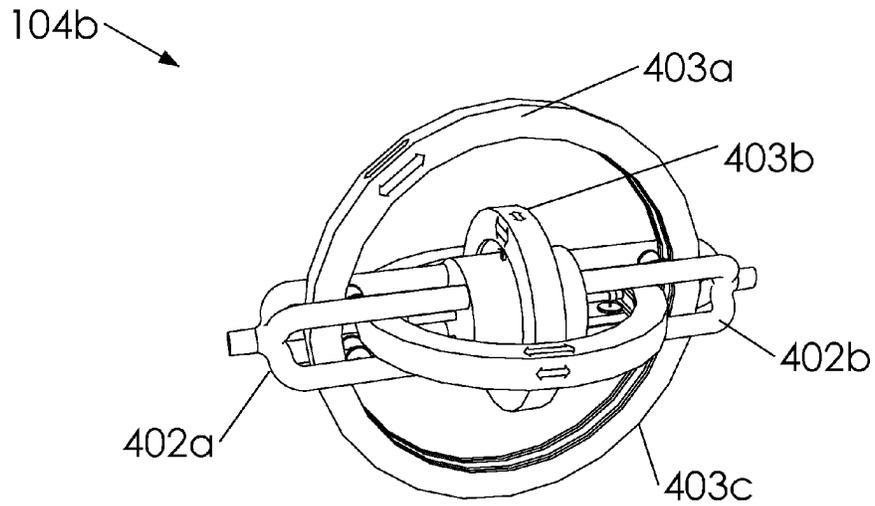


Fig. 4A

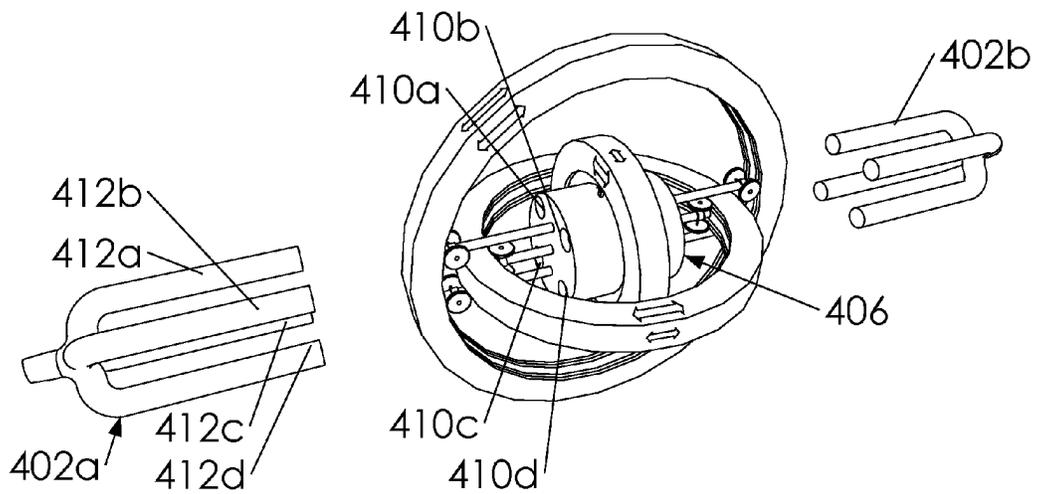


Fig. 4B

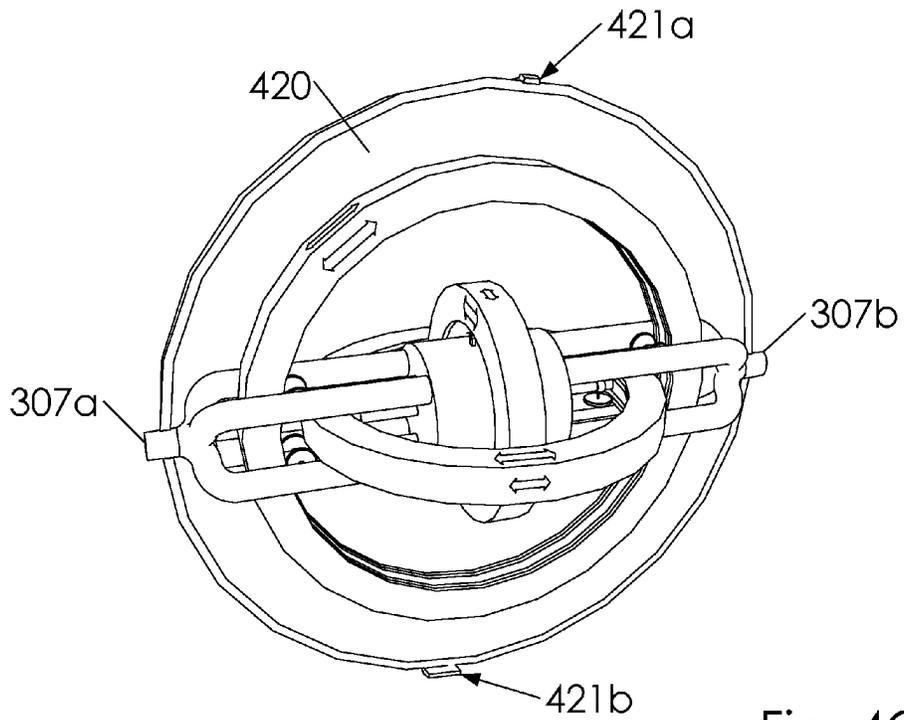


Fig. 4C

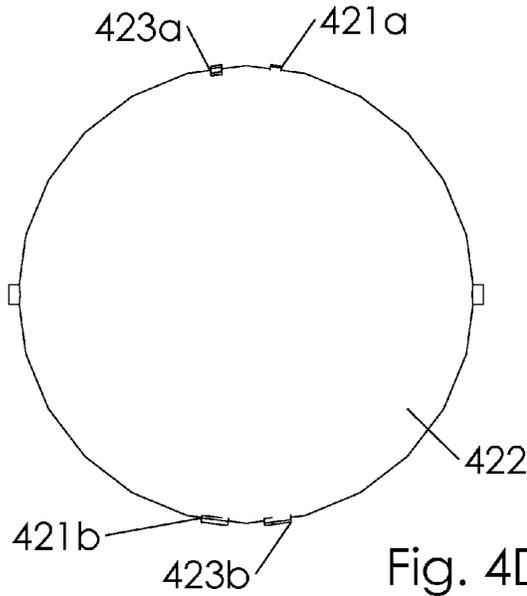


Fig. 4D

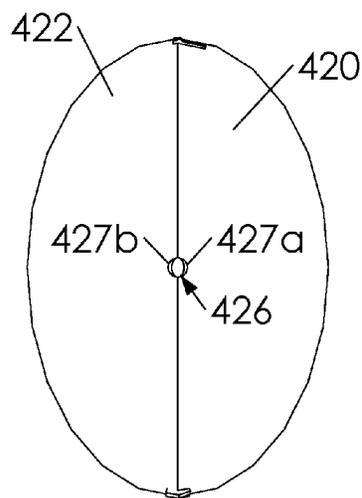


Fig. 4E

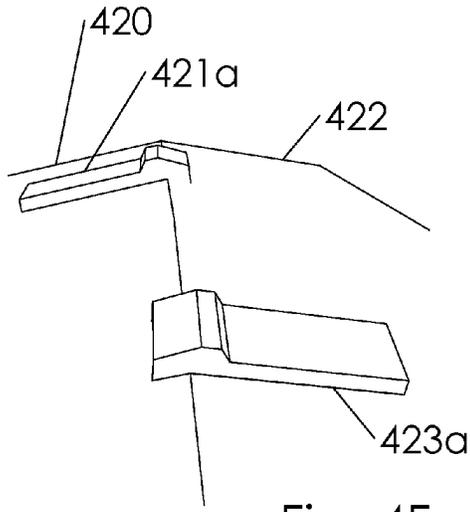


Fig. 4F

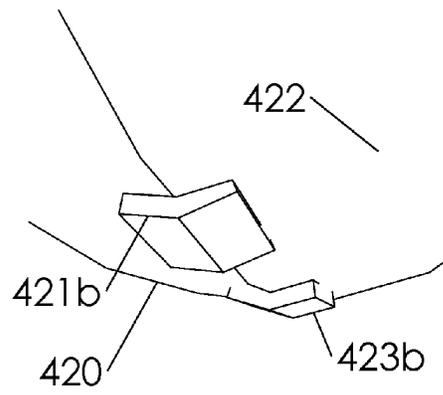


Fig. 4G

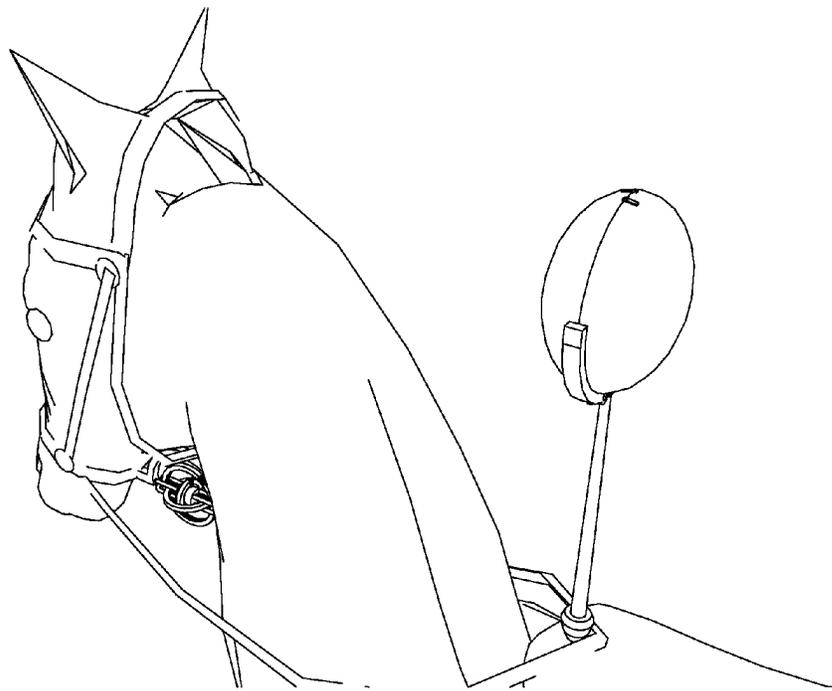


Fig. 4H

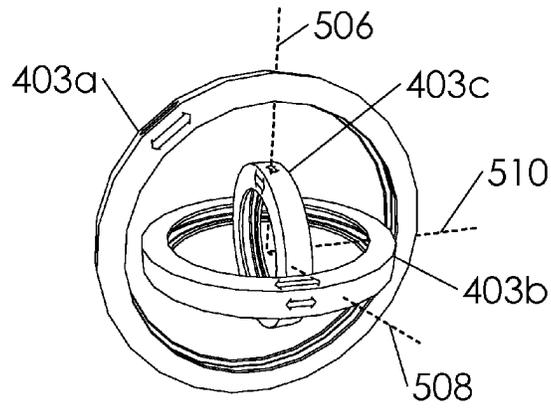


Fig. 5A

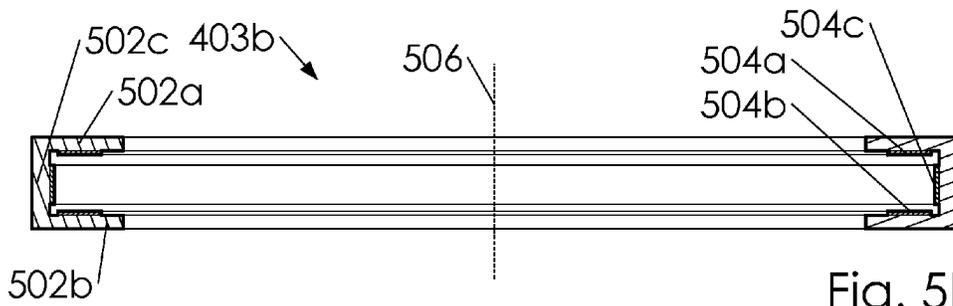


Fig. 5B

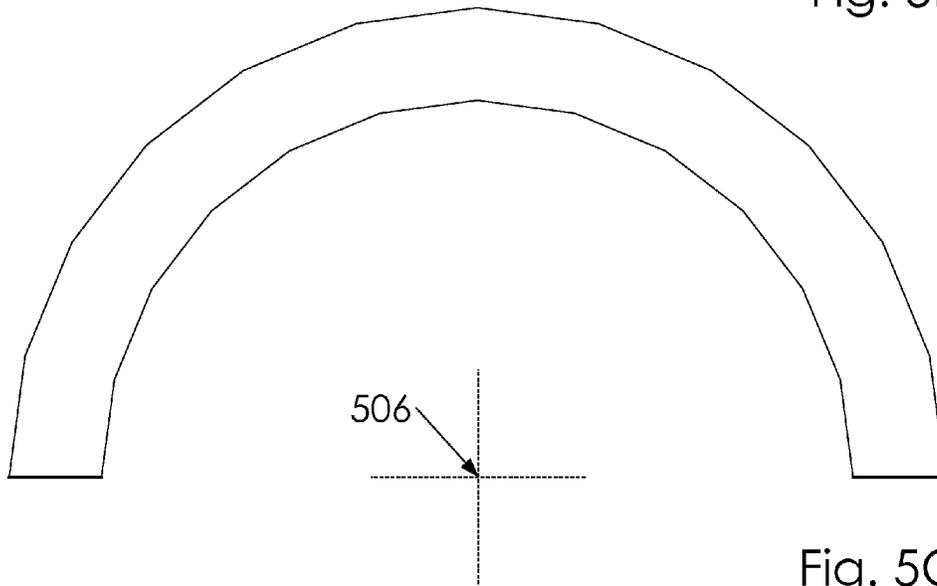


Fig. 5C

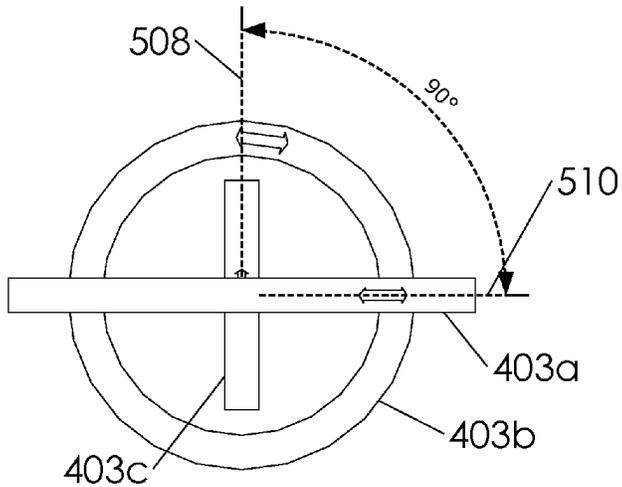


Fig. 5D

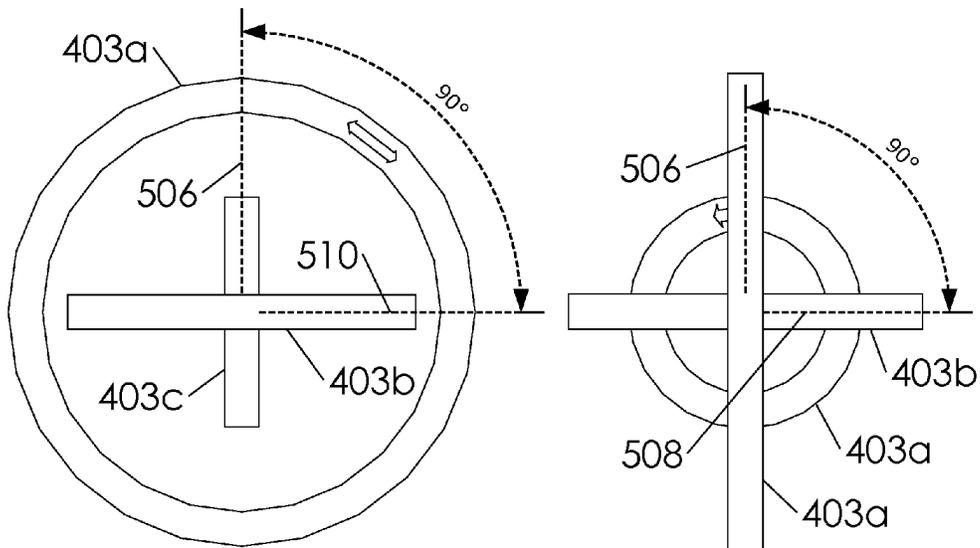


Fig. 5E

Fig. 5F

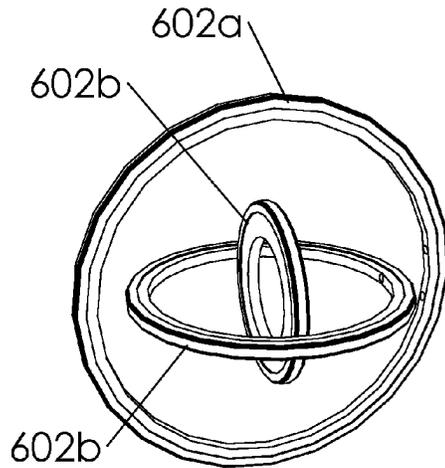


Fig. 6A

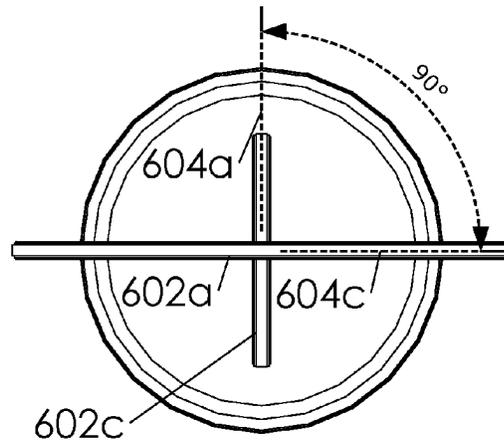


Fig. 6B

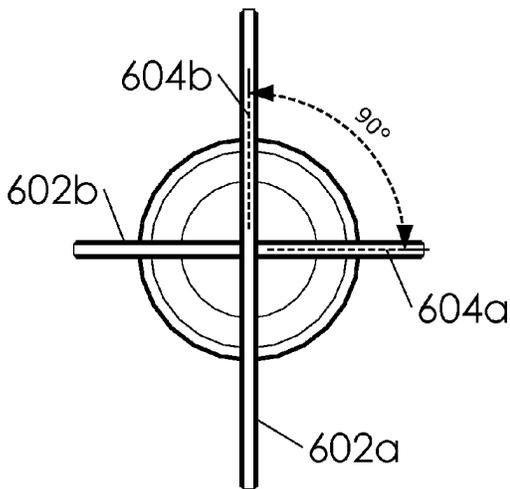


Fig. 6D

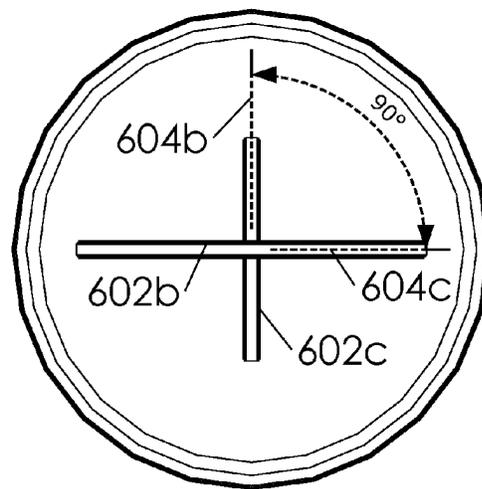


Fig. 6C

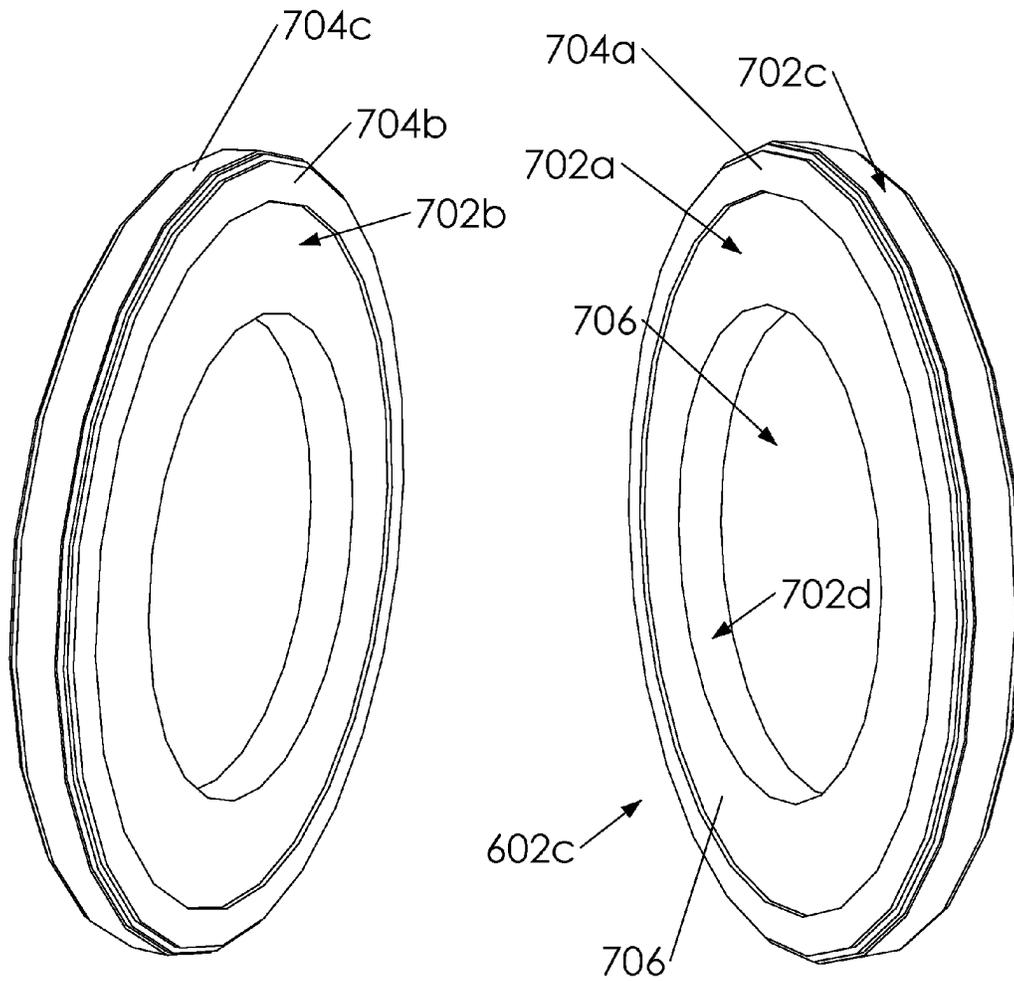


Fig. 7A

Fig. 7B

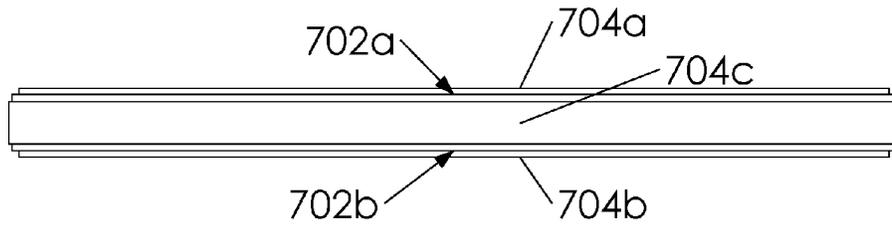


Fig. 7C

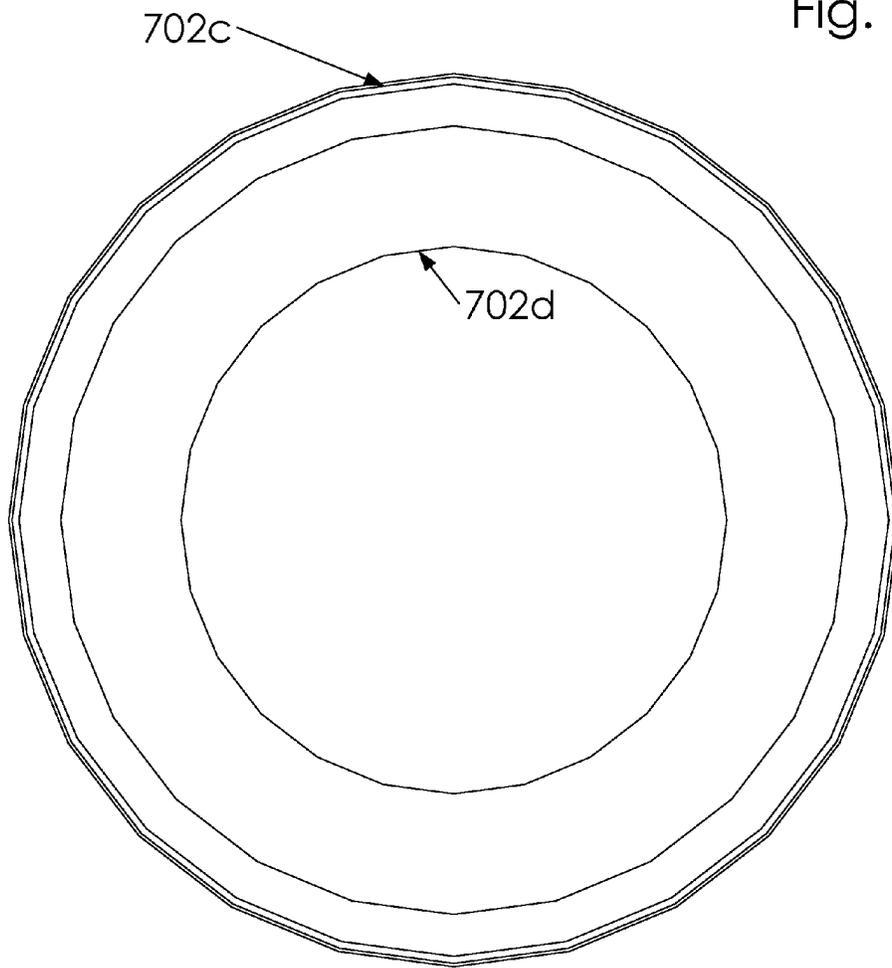


Fig. 7D

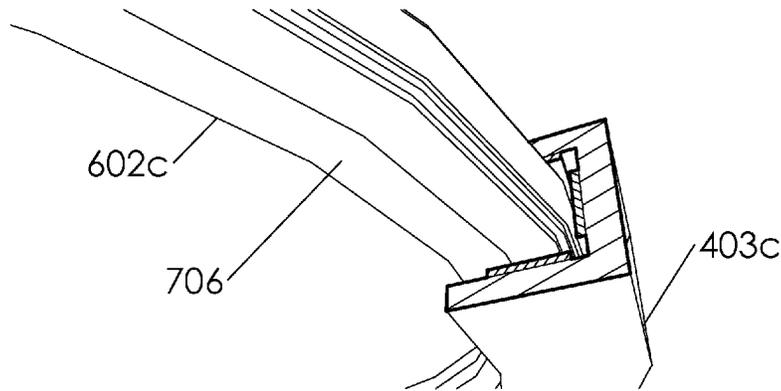


Fig. 8A

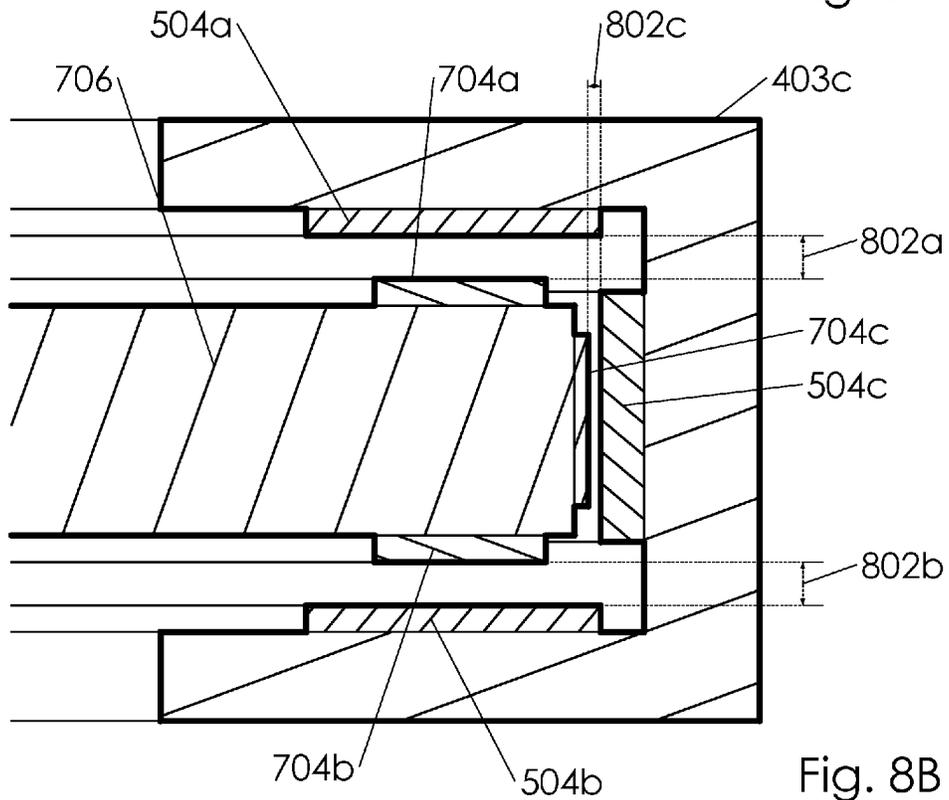


Fig. 8B

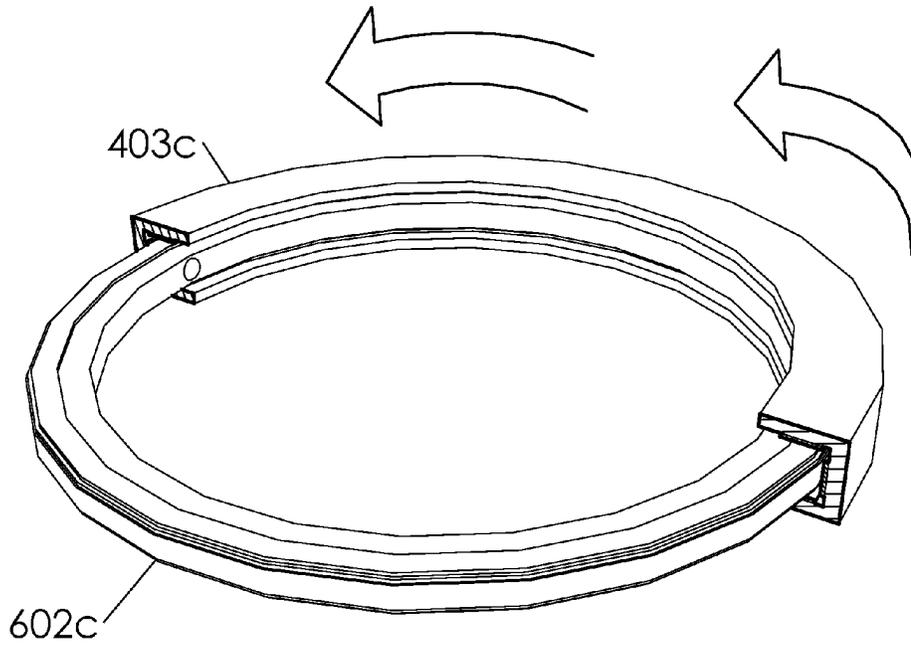


Fig. 9A

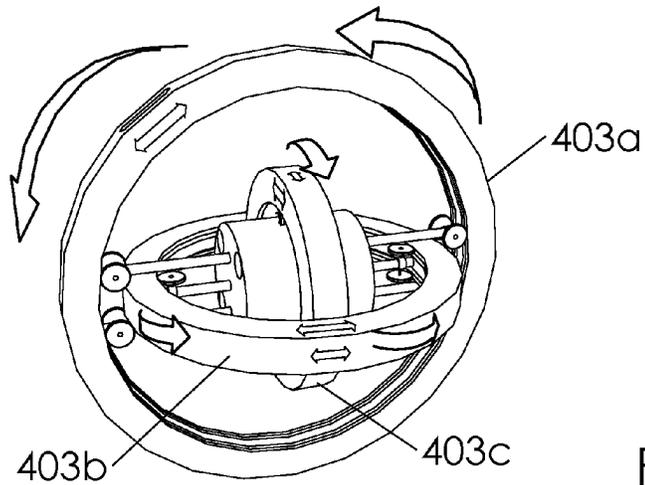


Fig. 9B

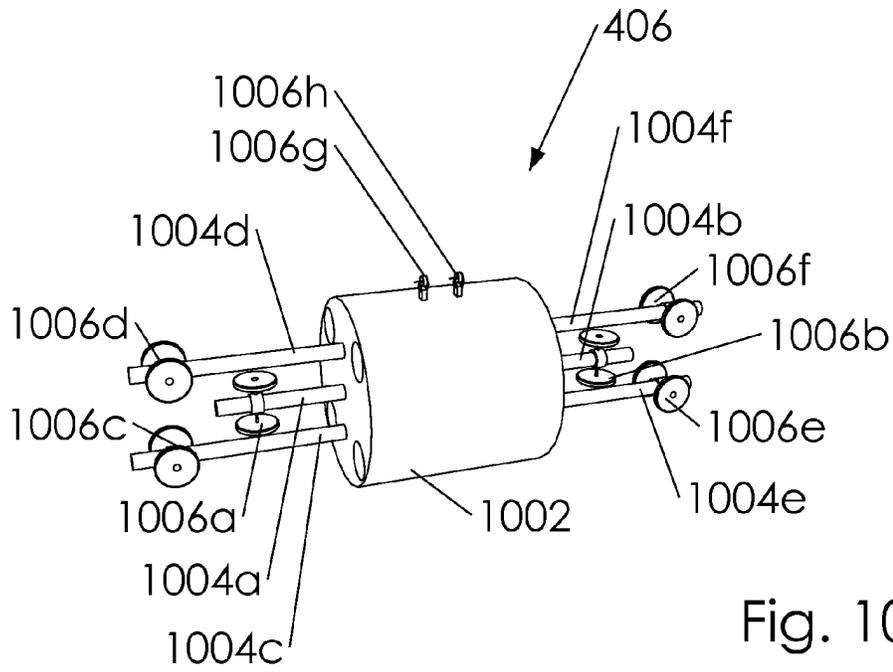


Fig. 10A

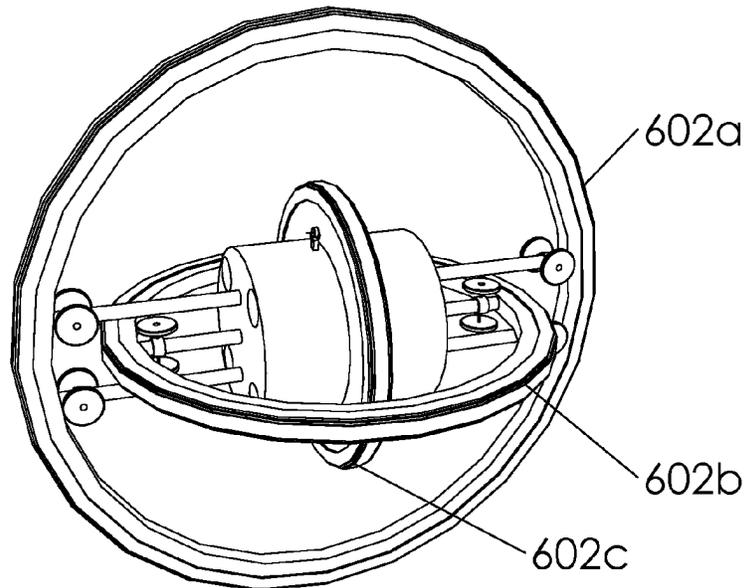


Fig. 10B

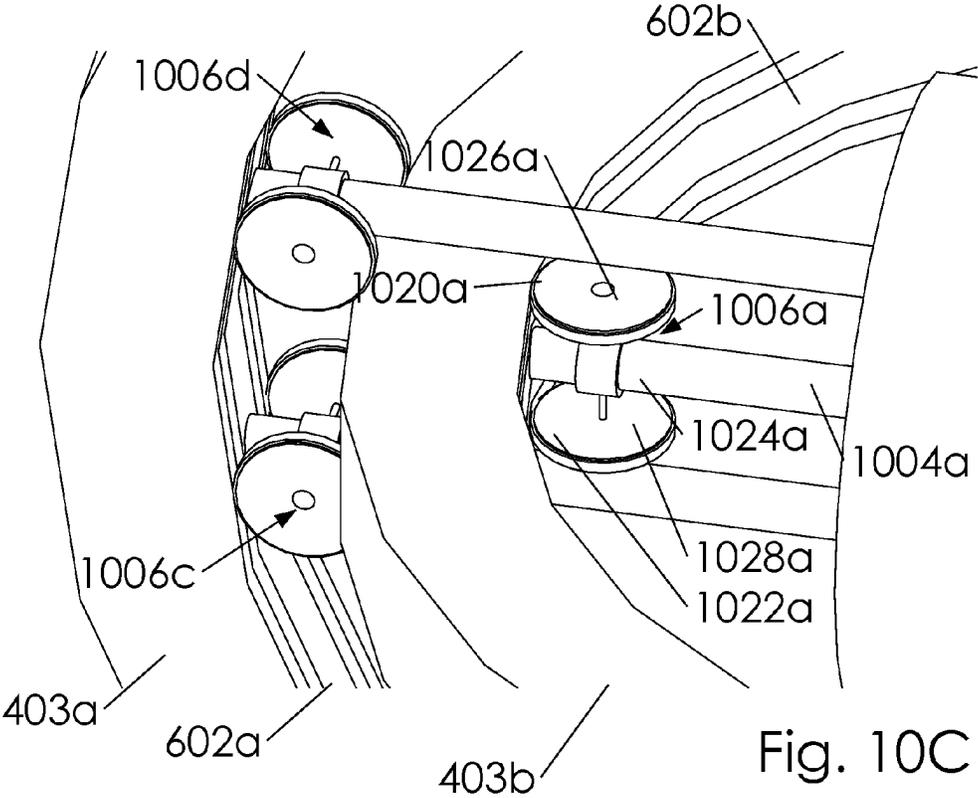


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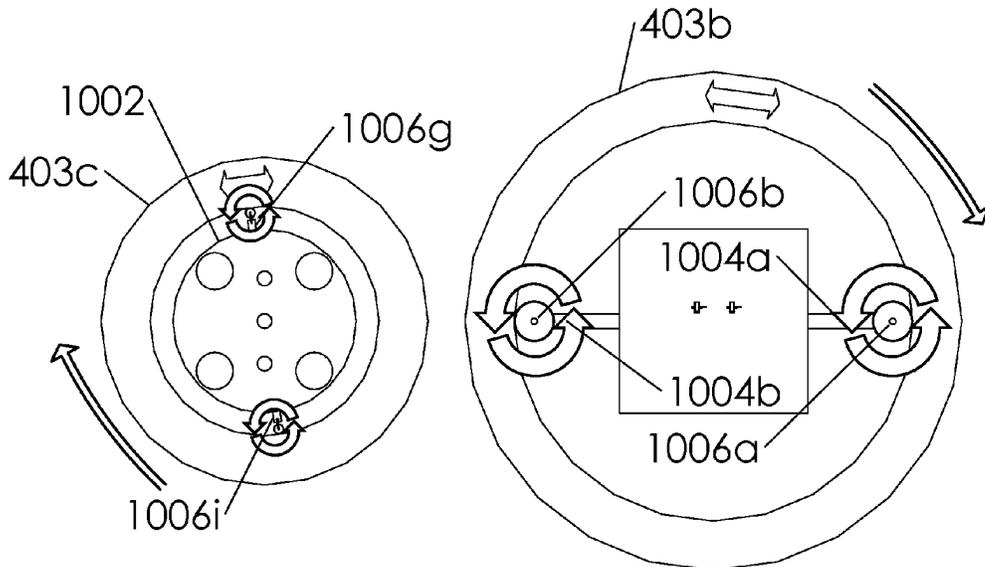


Fig. 10D

Fig. 10E

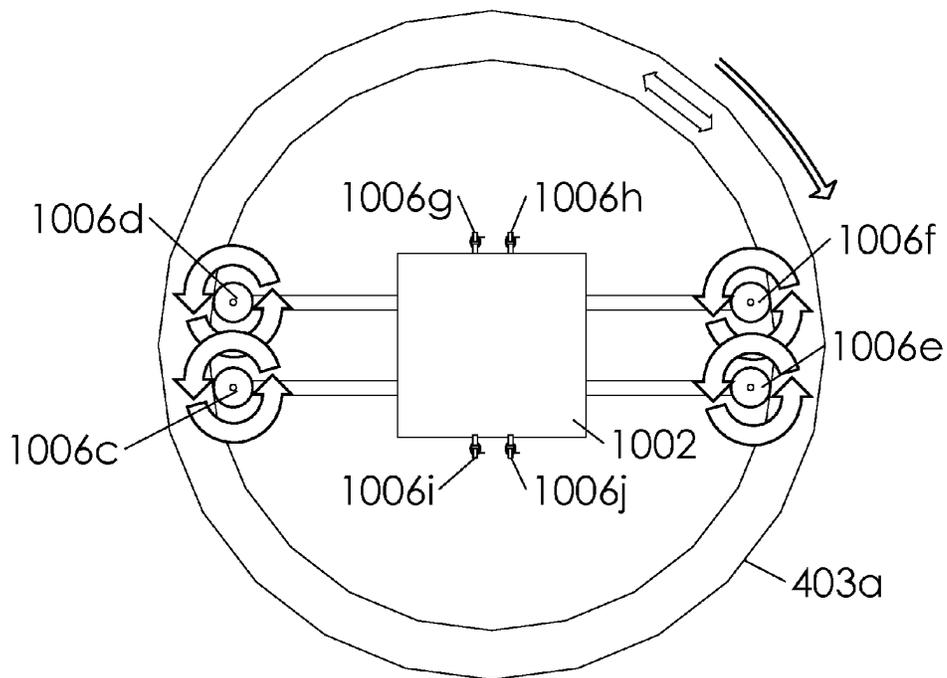


Fig. 10F

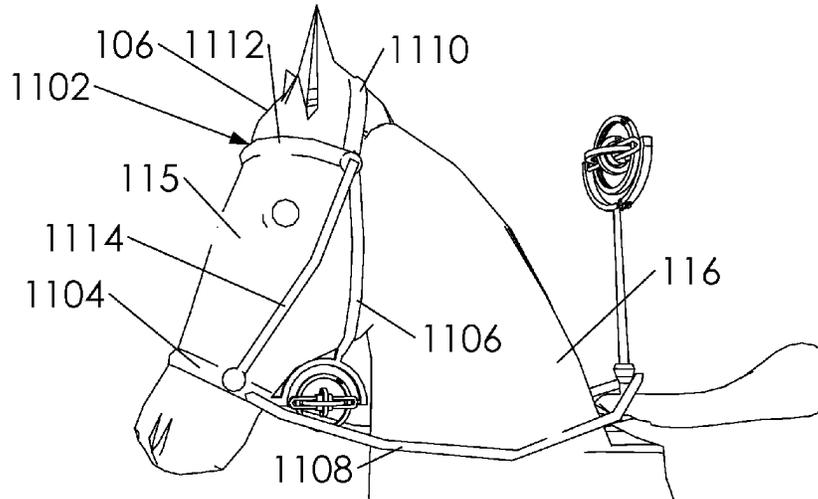


Fig. 11A

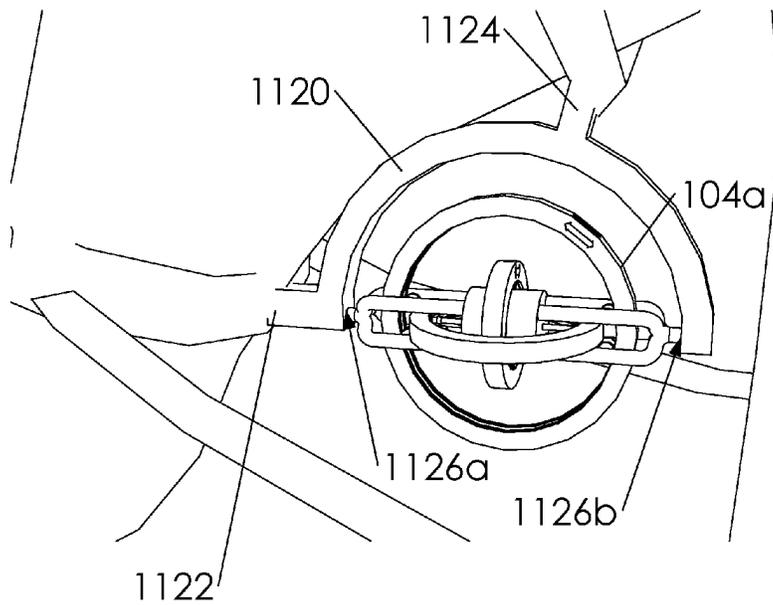


Fig. 11B

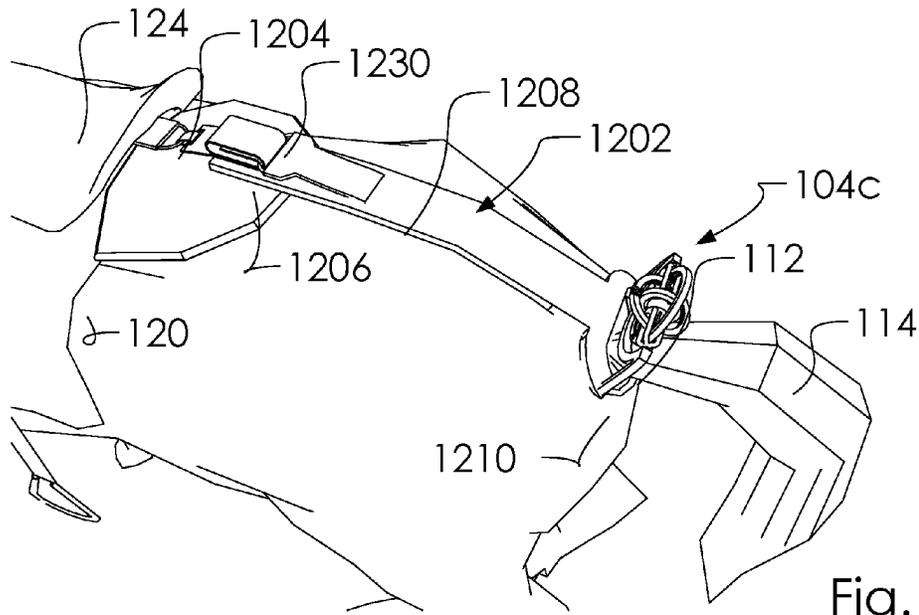


Fig. 12A

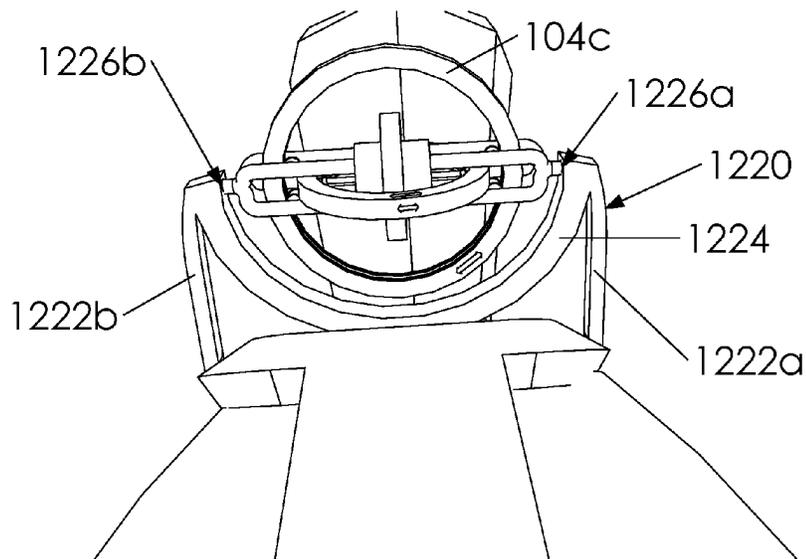


Fig. 12B

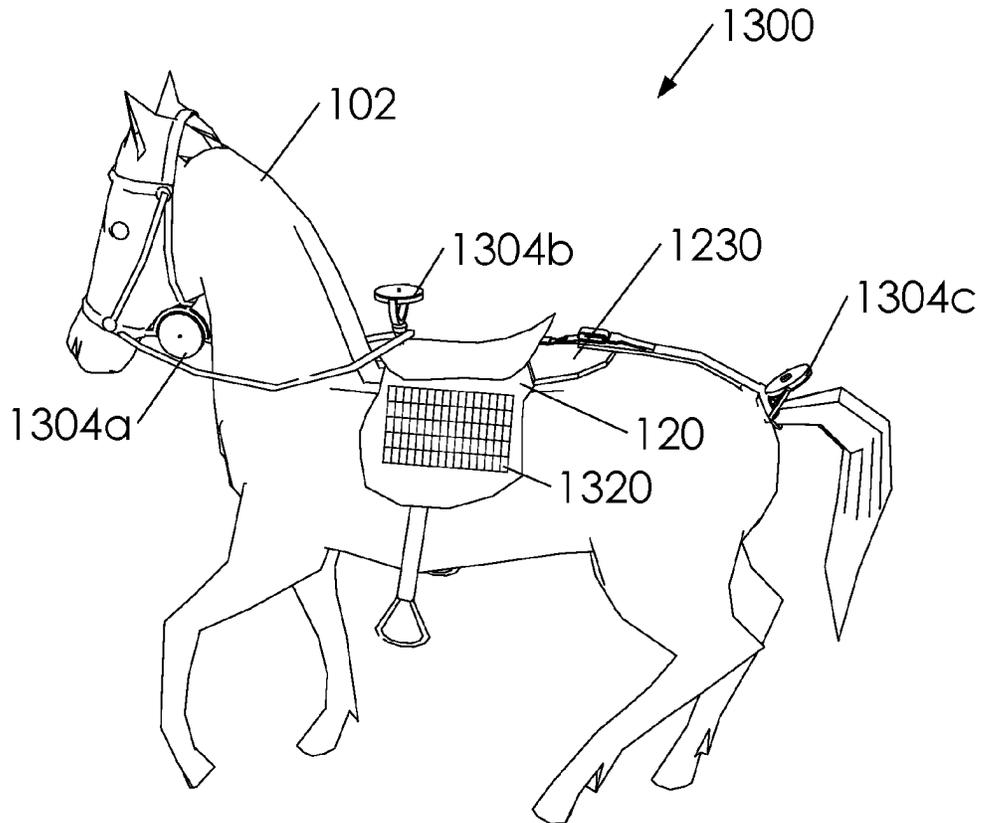


Fig. 13

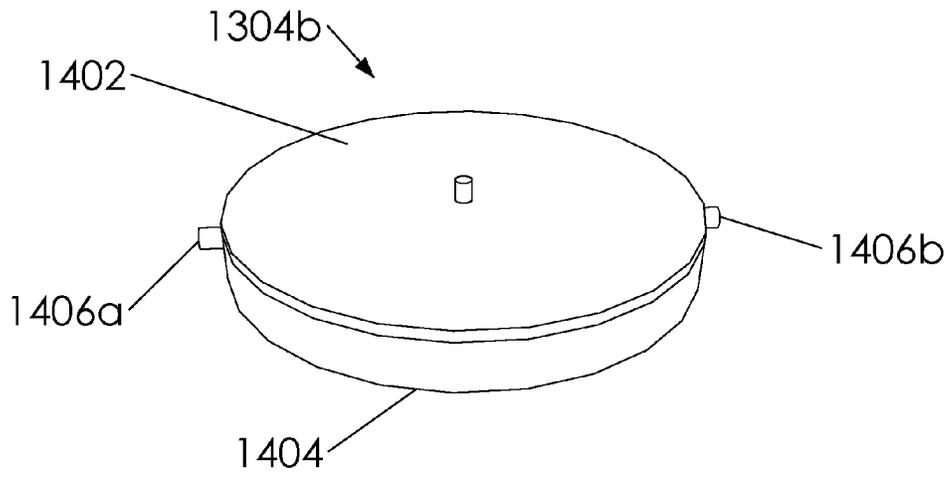


Fig. 14A

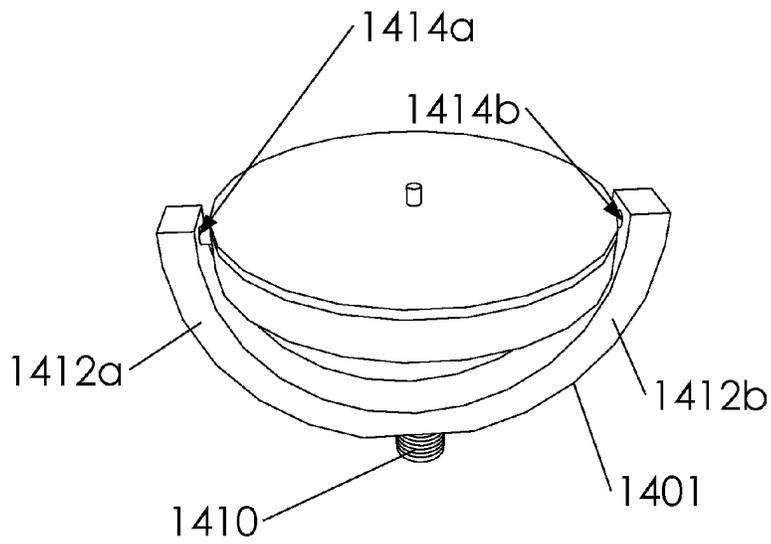


Fig. 14B

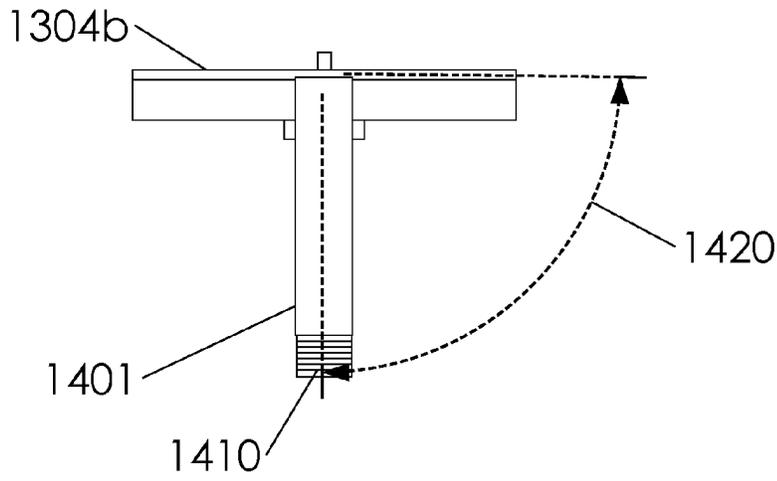


Fig. 14C

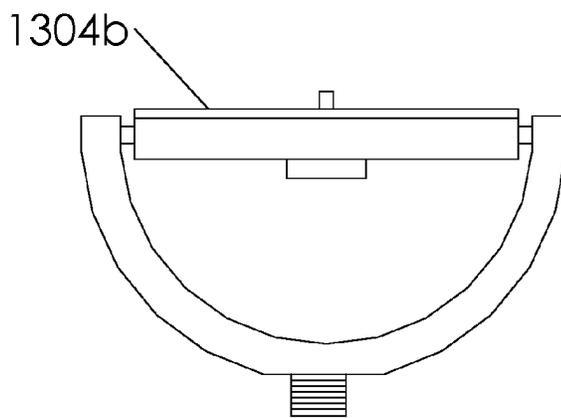


Fig. 14D

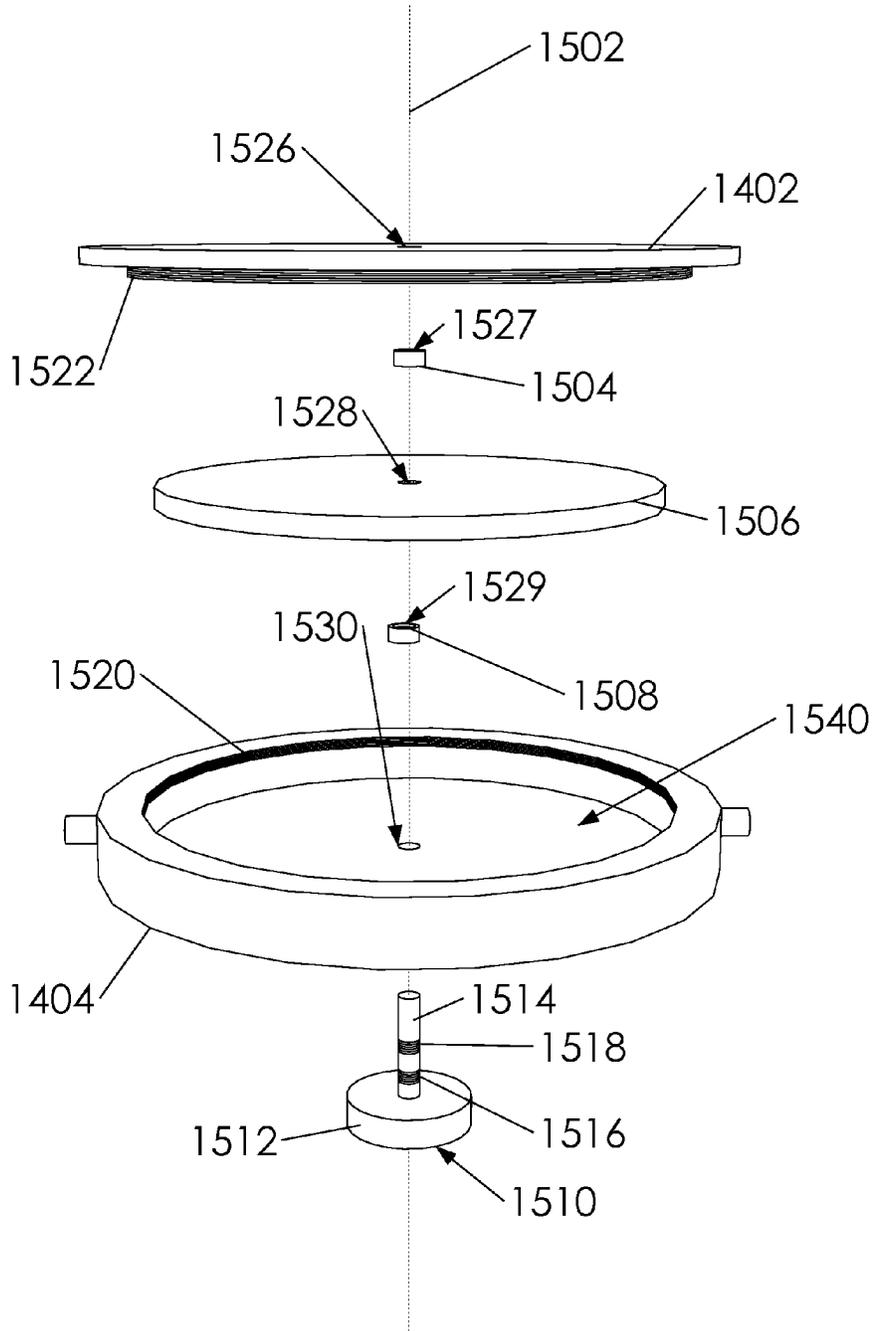


Fig. 15A

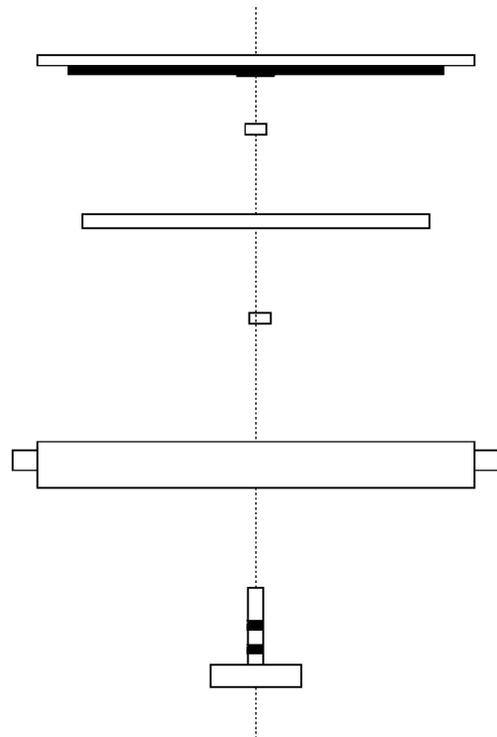


Fig. 15B

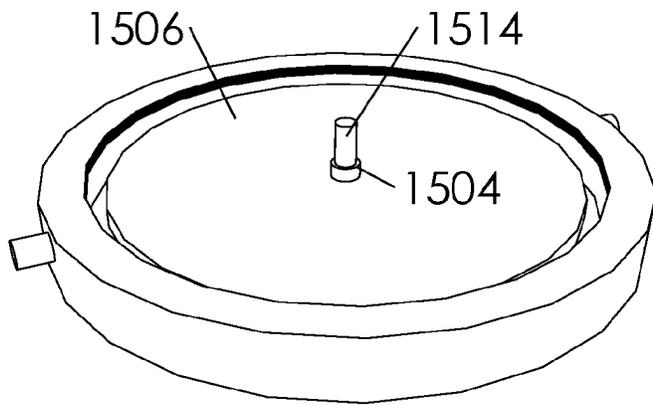


Fig. 15C

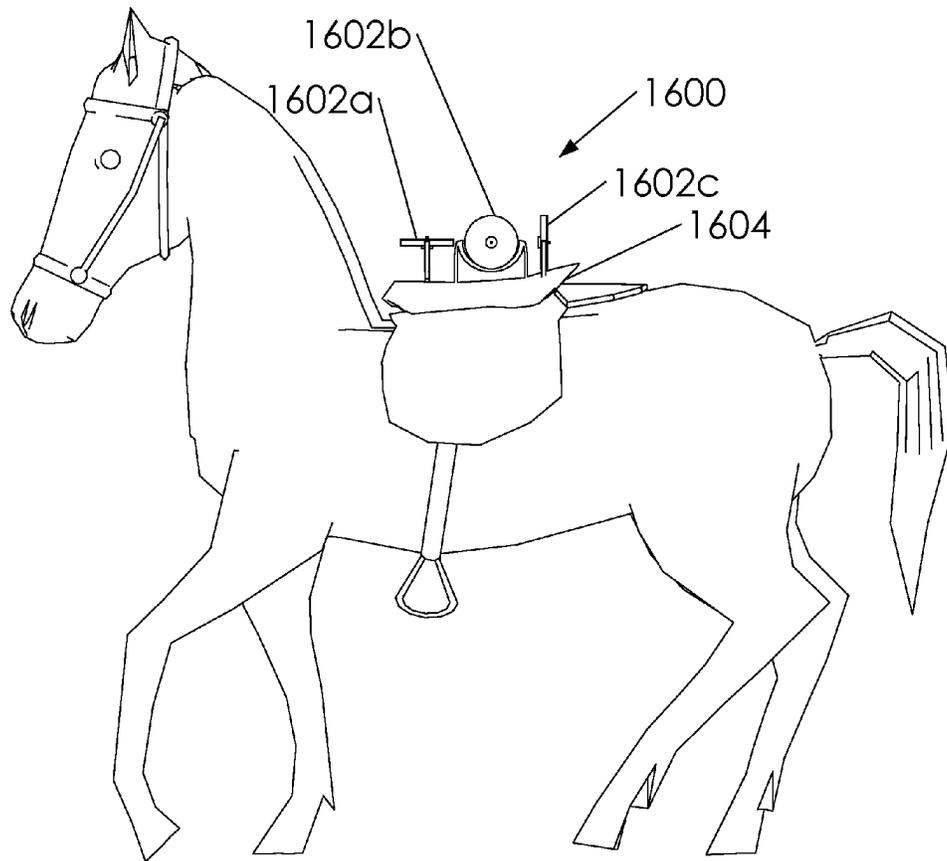


Fig. 16A

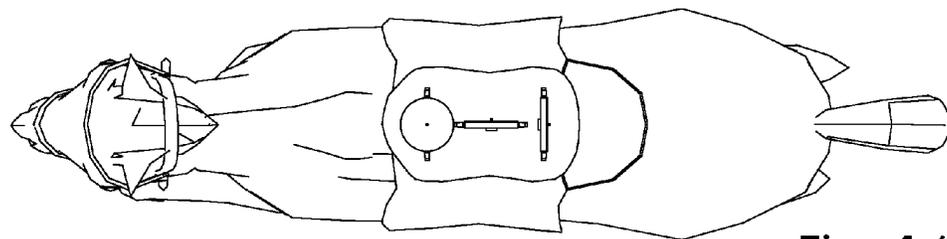


Fig. 16B

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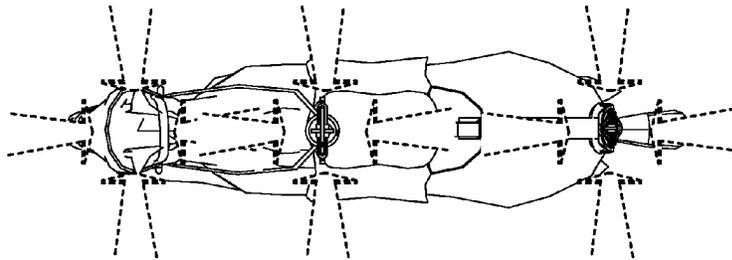


Fig. 17A

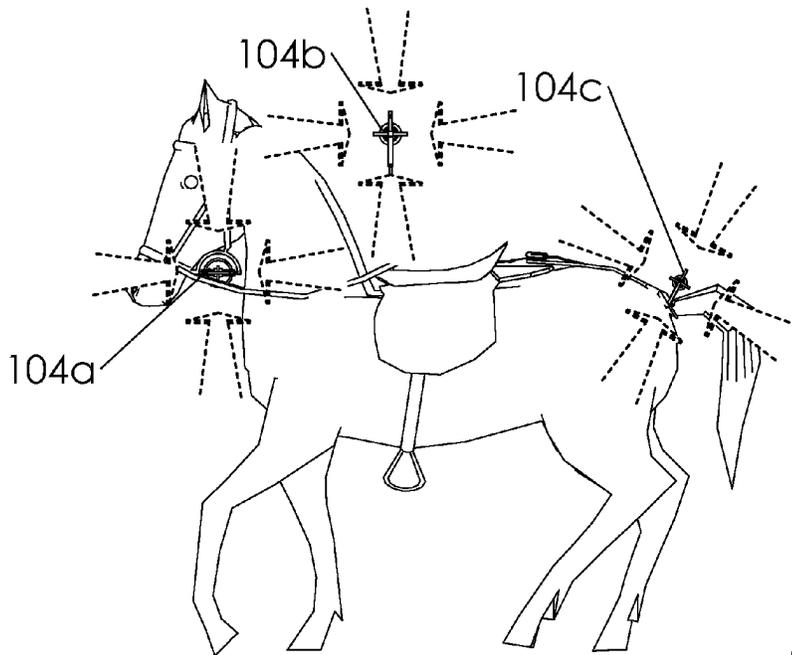


Fig. 17B

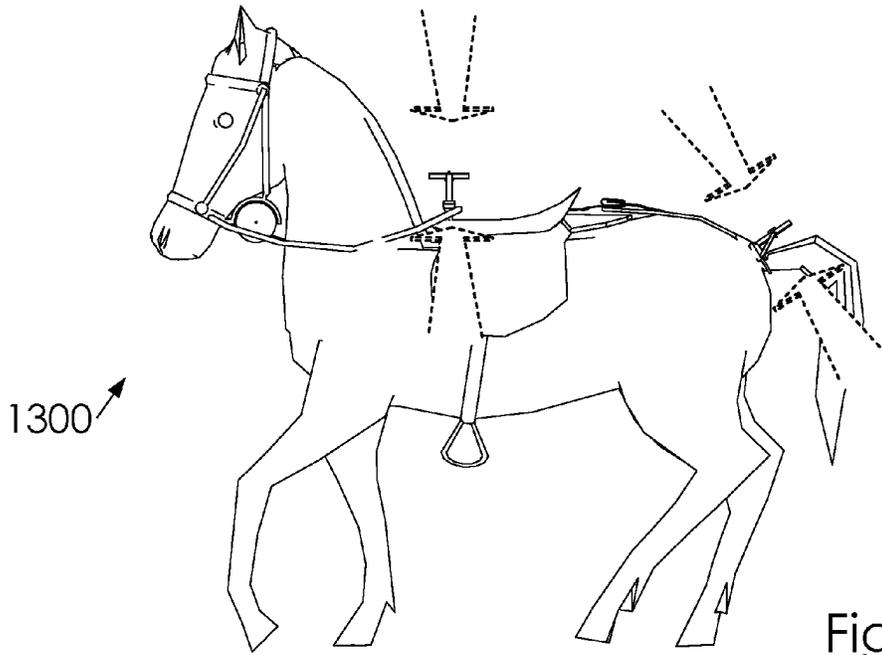


Fig. 18A

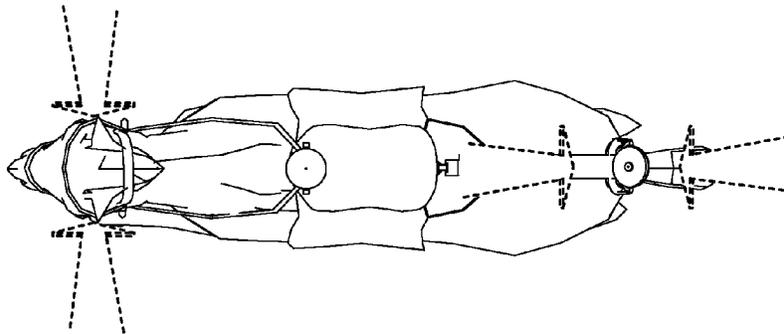


Fig. 18B

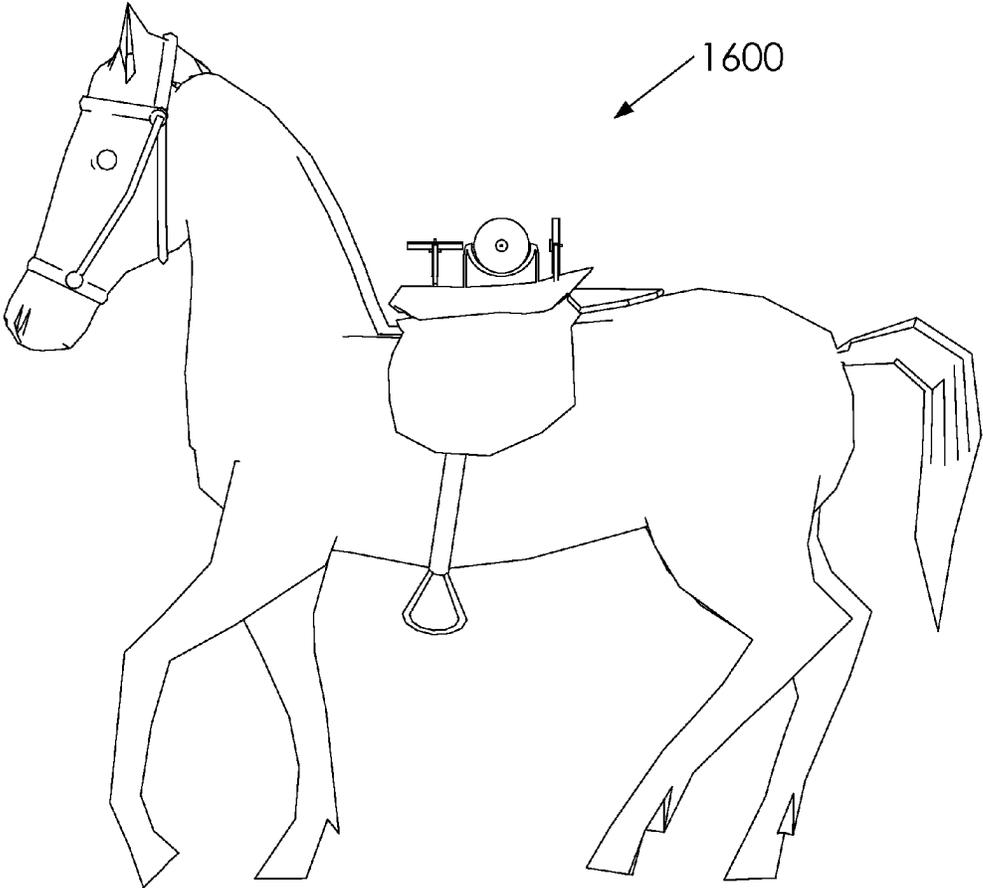


Fig. 19A

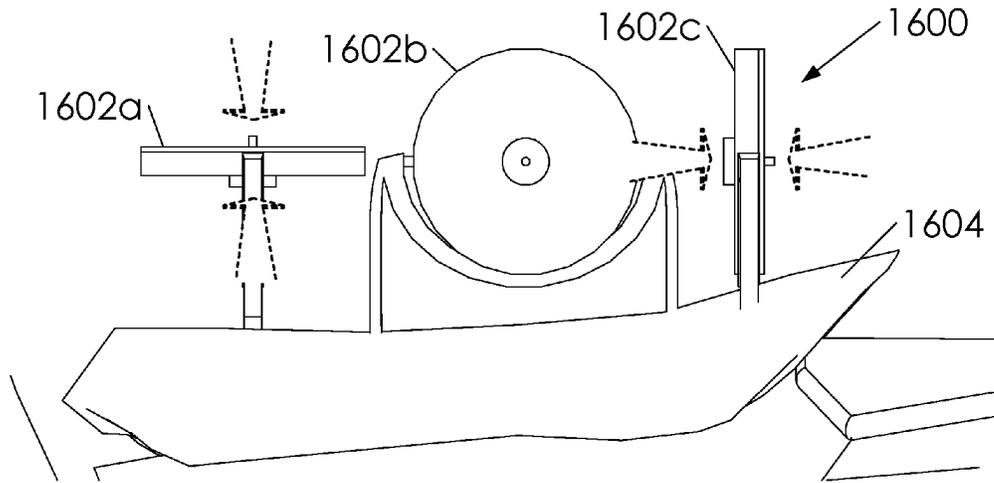


Fig. 19B

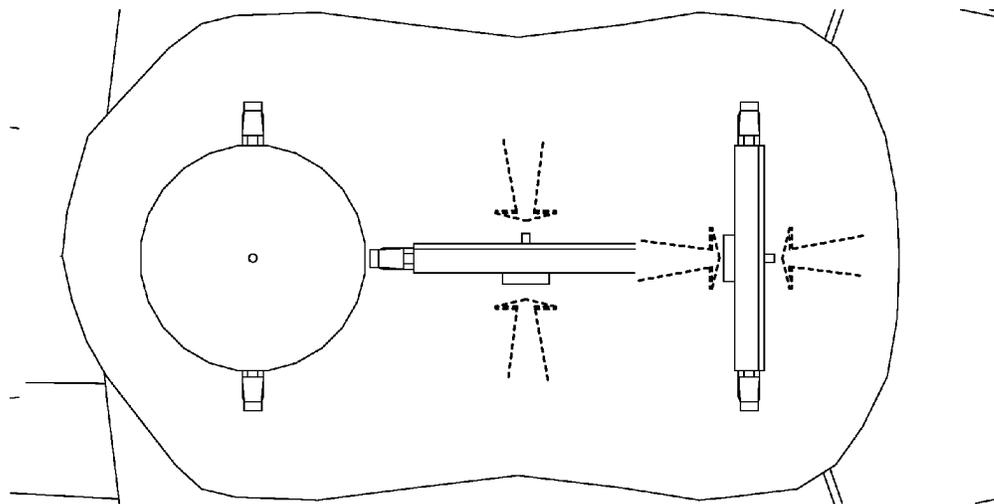


Fig. 19C

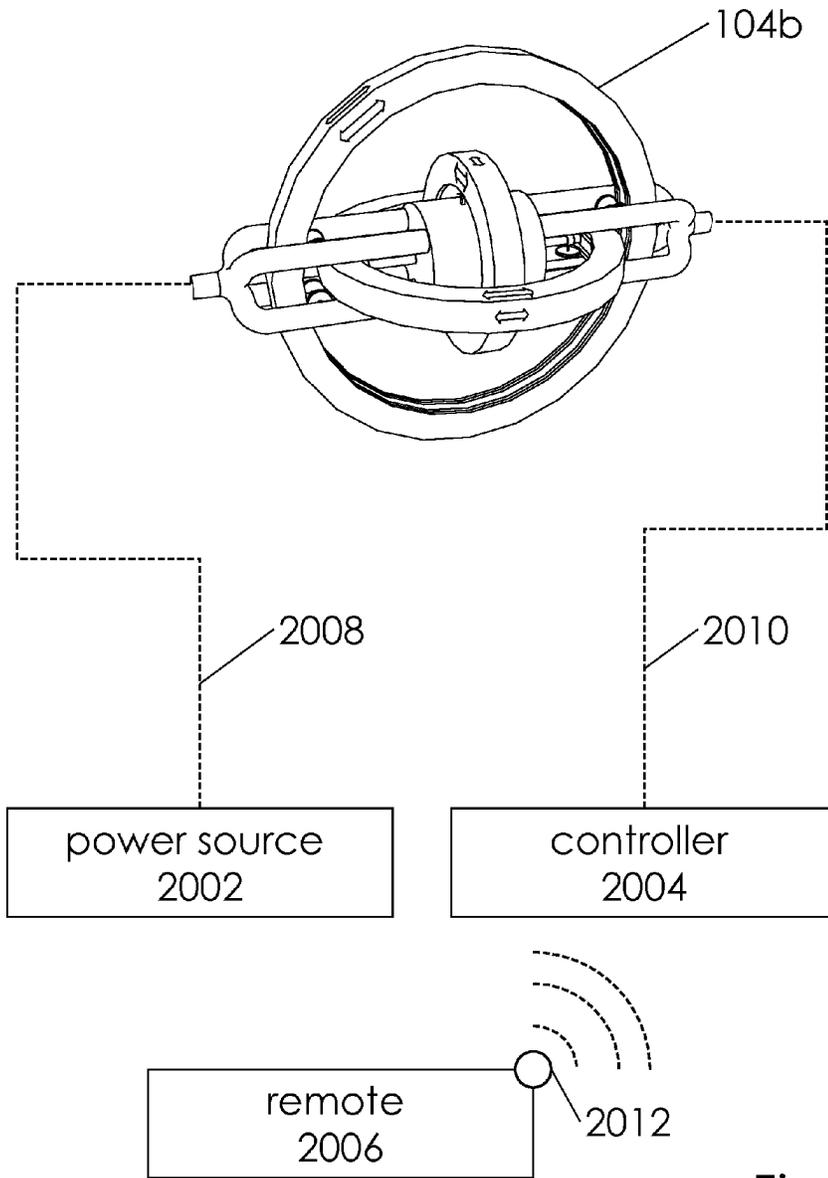


Fig. 20

1

SYSTEM AND METHOD OF USE OF GYROSCOPIC FORCES ON ANIMAL EQUILIBRIUM

BACKGROUND

This disclosure relates generally to a system and method of use of gyroscopic forces on animal equilibrium. Animal training systems are well known and the mechanics and use of gyroscopic forces are also well known. However, the combination and use of these arts are as yet unexplored as herein disclosed.

An example of an animal training system can be found in U.S. Pat. No. 3,942,477. In that patent application, Mr. Richardson quoted Mr. John Solomon Rarey (a horse trainer of the 19th century) who said: "The horse is so constituted by nature that he will not offer resistance to any demand made of him which he fully comprehends That we can, in compliance with the laws of his nature, by which he examines all things new to him, take any object, however frightful, around, or on him that does not inflict pain, without causing him to fear."

None of the prior inventions and patents, taken either singularly or in combination, is seen to describe the instant disclosure as claimed. Thus, a system and method of use of gyroscopic forces on animal equilibrium is desirable.

SUMMARY

An animal training system, an animal training method and an animal stabilization system are disclosed.

Said animal training system comprises a one or more gyroscopic assemblies each having a one or more rotors, a one or more gyroscope brackets, a power source attached to a one or more engines, and a one or more angular momentum forces. Said one or more rotors each comprise an axis. Said one or more gyroscope brackets attaching said one or more gyroscopic assemblies to an animal. Said one or more engines transmit a torque to said one or more rotors. Said one or more angular momentum forces are generated by rotating said one or more rotors in said one or more gyroscopic assemblies.

Said animal training method comprises: attaching one or more gyroscopic assemblies each having a one or more rotors to an animal; rotating said one or more external rotors with one or more engines; generating a one or more angular momentum forces with said one or more one or more external rotors; directing said one or more angular momentum forces at one or more parts of a body of said animal; and training said animal.

Said animal stabilization system comprises a one or more gyroscopic assemblies each having a one or more rotors, a one or more gyroscope brackets, a power source attached to a one or more engines, and a one or more angular momentum forces. Said one or more rotors each comprise an axis. Said one or more gyroscope brackets attaching said one or more gyroscopic assemblies to an animal. Said one or more engines transmit a torque to said one or more rotors. Said one or more angular momentum forces are generated by rotating said one or more rotors in said one or more gyroscopic assemblies.

BRIEF DESCRIPTION OF THE DRAWINGS

FIG. 1A illustrates a perspective overview of an animal training system on an animal.

FIG. 1B illustrates a plurality of sensory locations on said animal.

FIGS. 2A, 2B, 2C and 2D illustrate a series of perspective overviews of said second gyroscopic assembly.

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FIGS. 3A-3H illustrate a series of perspective views of said horn mount assembly attaching to said first gyroscopic assembly.

FIG. 3A illustrates a perspective overview of said first gyroscopic assembly unattached to said horn mount assembly.

FIGS. 3B and 3C illustrate a detailed perspective view of said first socket of said gyroscope bracket and a detailed perspective side view of said first prong of said second gyroscopic assembly.

FIGS. 3D and 3E illustrate a perspective overview of a hinge assembly of said gyroscope bracket.

FIGS. 3F, 3G and 3H illustrate a perspective lower view of said hinge assembly in an unlatched and open configuration, a closed and unlatched configuration, and a closed and latched configuration.

FIGS. 4A-4G illustrate a series of views of said first gyroscopic assembly.

FIGS. 4A and 4B illustrate a perspective overview of said second gyroscopic assembly with two framing members.

FIGS. 4C, 4D and 4E illustrate a perspective overview of said second gyroscopic assembly with a first casing, an elevated front view and an elevated side view of said second gyroscopic assembly with said first casing and a second casing.

FIGS. 4F and 4G illustrate a perspective top side view of said first clip and said first clip, and a perspective bottom side view of said second clip and said second clip.

FIG. 4H illustrates said second gyroscopic assembly on said animal comprising said casing assembly.

FIGS. 5A, 5B and 5C illustrate a perspective overview and an elevated cross-section front and top view of said second external rotor.

FIGS. 5D, 5E and 5F illustrate an elevated top view, an elevated front view, and an elevated side view of said one or more external rotors.

FIGS. 6A, 6B, 6C and 6D illustrate a perspective overview, an elevated top view, an elevated front view, and an elevated side view of one or more internal rails.

FIGS. 7A, 7B, 7C and 7D illustrate a perspective first side view, a perspective second side view, an elevated top view and an elevated front view of said third internal rail.

FIGS. 8A and 8B illustrate a perspective overview of said third internal rail within a cross-section view of said third external rotor, and an elevated cross-section view of said third internal rail and said third external rotor.

FIGS. 9A and 9B illustrate a perspective overview of a cross-section of said third external rotor arranged around said third internal rail and a perspective overview of said one or more gyroscopic assemblies.

FIGS. 10A and 10B illustrate said a perspective overview of said internal assembly and said internal assembly with said one or more internal rails.

FIGS. 10C and 10D illustrate said one or more wheels interfacing with said one or more external rotors.

FIGS. 10D, 10E and 10F illustrate an elevated side view of said third external rotor with said central portion; an elevated top view of said central portion with said second external rotor, said first leg and said second leg; and an elevated front view of said central portion with said third leg, fourth leg, said fifth leg, said sixth leg and said first external rotor.

FIGS. 11A and 11B illustrate a perspective front overview of said, and a detailed perspective front overview of said first gyroscopic assembly.

FIGS. 12A and 12B illustrate a perspective overview and perspective top view of said third gyroscopic assembly.

FIG. 13 illustrates a perspective overview of said animal with an animal training system.

FIGS. 14A, 14B, 14C and 14D illustrate a perspective overview of said second gyroscopic assembly without a gyroscope bracket, a view with said gyroscope bracket, an elevated side view and an elevated front view with said gyroscope bracket.

FIGS. 15A, 15B and 15C illustrate a perspective exploded overview and an elevated front side view of said second gyroscopic assembly, and a partially assembled perspective overview of said second gyroscopic assembly without said upper casing.

FIGS. 16A and 16B illustrate an elevated front view and top view of an animal training system.

FIGS. 17A and 17B illustrate an elevated top view and side view of said animal training system on said animal.

FIGS. 18A and 18B illustrate an elevated side view and top view of said animal training system on said animal.

FIGS. 19A, 19B and 19C illustrate an elevated side overview, an elevated detail side view and top view of said animal training system.

FIG. 20 illustrates a power and control schematic for one of said one or more gyroscopic assemblies.

DETAILED DESCRIPTION

Described herein is a system and method of use of gyroscopic forces on animal equilibrium. The following description is presented to enable any person skilled in the art to make and use the invention as claimed and is provided in the context of the particular examples discussed below, variations of which will be readily apparent to those skilled in the art. In the interest of clarity, not all features of an actual implementation are described in this specification. It will be appreciated that in the development of any such actual implementation (as in any development project), design decisions must be made to achieve the designers' specific goals (e.g., compliance with system- and business-related constraints), and that these goals will vary from one implementation to another. It will also be appreciated that such development effort might be complex and time-consuming, but would nevertheless be a routine undertaking for those of ordinary skill in the field of the appropriate art having the benefit of this disclosure. Accordingly, the claims appended hereto are not intended to be limited by the disclosed embodiments, but are to be accorded their widest scope consistent with the principles and features disclosed herein.

FIG. 1A illustrates a perspective overview of an animal training system 100 on an animal 102. In one embodiment, said system and method of use of gyroscopic forces on animal equilibrium can comprise said animal training system 100. In one embodiment, said animal training system 100 can comprise one or more gyroscopic assemblies. In one embodiment, said one or more gyroscopic assemblies can comprise a first gyroscopic assembly 104a, a second gyroscopic assembly 104b and a third gyroscopic assembly 104c. Said animal 102 can comprise a head 106, a body 108, a buttock 110, a tail head 112, a tail 114, a muzzle 115, a neck 116 and a back 118. In one embodiment, said animal 102 can comprise a horse, but said animal training system 100 can be used on a variety of animals other than horses. In one embodiment, said animal 102 can comprise a dog, livestock, or other animal. In one embodiment, said animal 102 can be fitted with a saddle 120 on said back 118 of said animal 102. In one embodiment, said saddle 120 can comprise a horn 122 and a seat 124, as known in the art.

FIG. 1B illustrates a plurality of sensory locations on said animal 102. In one embodiment, said animal training system 100 can attach to said animal 102 at a plurality of sensory locations. In one embodiment, said plurality of sensory locations can comprise a forward sensory location 130a, a central sensory location 130b and a rear sensory location 130c. In one embodiment, said plurality of sensory locations can comprise locations on said animal 102 corresponding to a sense of equilibrium on said animal 102. In one embodiment, said animal 102 can comprise a forward portion 132, a midsection 134 and a rearward portion 136 of said body 108. In one embodiment, said one or more gyroscopic assemblies can be attached to any part of said body 108 of said animal 102. In one embodiment, said first gyroscopic assembly 104a can attach to said forward portion 132, said second gyroscopic assembly 104b can attach to said midsection 134, and said third gyroscopic assembly 104c can attach to said rearward portion 136 of said body 108 of said animal 102.

FIGS. 2A, 2B, 2C and 2D illustrate a series of perspective overviews of said second gyroscopic assembly 104b. In one embodiment, second gyroscopic assembly 104b can attach to said horn 122 with a horn mount assembly 200. In one embodiment, said horn mount assembly 200 can comprise a shaft 202 (having a first end 203a and a second end 203b) and a gyroscope bracket 204. In one embodiment, said second end 203b can comprise a base portion 205 having an external threading 206. In one embodiment, said first end 203a attaches to said gyroscope bracket 204. In one embodiment, said shaft 202 can comprise a cylindrical rod. In one embodiment, said horn 122 can comprise a socket 208 having an internal threading 210. In one embodiment, said base portion 205 of said shaft 202 can attach to said horn 122. In one embodiment, said external threading 206 of said base portion 205 can attach to said internal threading 210 of said socket 208.

In one embodiment, said animal training system 100 can comprise a one or more gyroscope brackets capable of attaching said one or more gyroscopic assemblies to said animal 102. In one embodiment, said one or more gyroscope brackets can comprise said gyroscope bracket 204.

FIGS. 3A-3H illustrate a series of perspective views of said horn mount assembly 200 attaching to said first gyroscopic assembly 104a.

FIG. 3A illustrates a perspective overview of said first gyroscopic assembly 104a unattached to said horn mount assembly 200. In one embodiment, said gyroscope bracket 204 can comprise a first side portion 302a and a second side portion 302b. In one embodiment, said first side portion 302a can comprise a first socket 304a, and said second side portion 302b can comprise a second socket 304b. In one embodiment, said gyroscope bracket 204 can comprise a "U" shape having said first side portion 302a as its first side with a first end 305a and said second side portion 302b as its second side having a second end 305b. In one embodiment, said gyroscope bracket 204 has an internal surface 306. In one embodiment, said first socket 304a and said second socket 304b can comprise a pair of sockets capable of receiving and holding a portion of one of said one or more gyroscopic assemblies (such as said second gyroscopic assembly 104b, illustrated). In one embodiment, said pair of sockets can be in said internal surface 306 of said gyroscope bracket 204 at said first end 305a and said second end 305b on opposing internal sides of said "U" shape. In one embodiment, said second gyroscopic assembly 104b can be substantially identical to each of said one or more gyroscopic assemblies. In one embodiment, said second gyroscopic assembly 104b can comprise two prongs. In one embodiment, said two prongs can comprise a first prong 307a and a second

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prong **307b**. In one embodiment, said two prongs of said second gyroscopic assembly **104b** can be inserted into said pair of sockets of said gyroscope bracket **204**. Alternatively, in one embodiment, one of said two prongs (for example said first prong **307a**), can be round rather than oval shaped in its cross-section and an external surface of said one of said two prongs can comprise an external threading; wherein, said one of said two prongs can attach to said socket **208** of said horn **122** by screwing said one of said two prongs into said internal threading **210** of said horn **122**.

FIGS. **3B** and **3C** illustrate a detailed perspective view of said first socket **304a** of said gyroscope bracket **204** and a detailed perspective side view of said first prong **307a** of said second gyroscopic assembly **104b**. In one embodiment, said first socket **304a** can comprise a width **320** and a height **322**. In one embodiment, said first prong **307a** can comprise a width **324** and a height **326**. In one embodiment, said first socket **304a** and said second socket **304b** can comprise similar dimensions. Likewise, in one embodiment, said first prong **307a** and said second prong **307b** can comprise similar dimensions. In one embodiment, said width **320** can be equal to or greater than said width **324**, and said height **322** can be equal to or greater than said height **326**. Accordingly, said first prong **307a** can slide into said first socket **304a**. In one embodiment, said width **320** and said height **322** can be dissimilar in size and therefore they can be oval shaped. Likewise, said width **324** and said height **326** can be dissimilar in size and therefore they can be oval shaped. In one embodiment, said height **326** can be greater than said width **320**. Accordingly, with said first prong **307a** inside of said first socket **304a**, said second gyroscopic assembly **104b** can be incapable of spinning within said pair of sockets in said gyroscope bracket **204**. Alternatively, in one embodiment, said pair of sockets and said two prongs can comprise a cross-section comprising a non-rounded shape (such as a rectangle, triangle or similar) and thereby prevent rotation while they are mated.

FIGS. **3D** and **3E** illustrate a perspective overview of a hinge assembly **330** of said gyroscope bracket **204**. In one embodiment, said gyroscope bracket **204** can comprise said hinge assembly **330**. In one embodiment, said hinge assembly **330** can open up said gyroscope bracket **204** so as to receive said first gyroscopic assembly **104a**. In one embodiment, said hinge assembly **330** can attach said first side portion **302a** to said second side portion **302b**. In one embodiment, said first side portion **302a** can rotate about said hinge assembly **330** while said second side portion **302b** remains relatively unmoved. In one embodiment, said second side portion **302b** attaches to said shaft **202**. In one embodiment, attaching said one or more gyroscopic assemblies to said gyroscope bracket **204** can comprise opening said gyroscope bracket **204** by releasing said hinge assembly **330** from in a closed configuration, inserting said second prong **307b** into said second socket **304b**, aligning said first prong **307a** with said first socket **304a**, and closing said gyroscope bracket **204** by latching said hinge assembly **330** with said gyroscope bracket **204** in said closed configuration. In one embodiment, said closed configuration of said gyroscope bracket **204** can comprise latching said hinge assembly **330** with said gyroscope bracket **204** in said "U" shape.

FIGS. **3F**, **3G** and **3H** illustrate a perspective lower view of said hinge assembly **330** in an unlatched and open configuration, a closed and unlatched configuration, and a closed and latched configuration. In one embodiment, said open configuration can comprise said hinge assembly **330** in a configuration other than said closed configuration. In one embodiment, said hinge assembly **330** can comprise an internal barrel **332**

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and an external barrel **334**. In one embodiment, said first side portion **302a** can comprise said internal barrel **332**, and said second side portion **302b** can comprise said external barrel **334**. In one embodiment, said internal barrel **332** can attach around said external barrel **334**, and said hinge assembly **330** can pivot around said external barrel **334**. In one embodiment, said hinge assembly **330** can further comprise a latch **336** and a latch track **338**. In one embodiment, said latch track **338** can be attached to said second side portion **302b** near said hinge assembly **330**. In one embodiment, latch **336** can slide in a lateral direction within said latch track **338**. In one embodiment, said latched configuration can comprise a portion of said latch **336** holding a portion of said first side portion **302a** in said closed configuration. In one embodiment, said unlatched configuration can comprise said latch **336** no longer holding said portion of said first side portion **302a** in said closed configuration. In one embodiment, said latch **336** can slide within said latch track **338** between said latched and said unlatched configurations. In one embodiment, said latch track **338** can comprise a track capable of wrapping around a portion of said latch **336** so as to hold said latch **336** between said latched configuration and said unlatched configuration.

FIGS. **4A-4G** illustrate a series of views of said first gyroscopic assembly **104a**. In one embodiment, said first gyroscopic assembly **104a** can comprise a representative example of said one or more gyroscopic assemblies.

FIGS. **4A** and **4B** illustrate a perspective overview of said second gyroscopic assembly **104b** with two framing members. In one embodiment, said two framing members can comprise a first framing member **402a** and a second framing member **402b**. In one embodiment, said two framing members can attach said second gyroscopic assembly **104b** to said gyroscope bracket **204**. In one embodiment, said first framing member **402a** can comprise first prong **307a**, and said second framing member **402b** can comprise said second prong **307b**. In one embodiment, said one or more gyroscopic assemblies can comprise one or more external rotors. In one embodiment, said one or more external rotors can comprise a first external rotor **403a**, a second external rotor **403b** and a third external rotor **403c**. In one embodiment, said one or more external rotors can comprise parts of one or more gyroscopes. In one embodiment, said first gyroscopic assembly **104a** can comprise said one or more gyroscopes. In one embodiment, said one or more gyroscopes can be aligned in one or more planes. In one embodiment, said one or more gyroscopes can be aligned in three planes, each being 90 degrees perpendicular to one another (as described below).

In one embodiment, said two framing members attach to an internal assembly **406** within said second gyroscopic assembly **104b**. In one embodiment, said internal assembly **406** can comprise one or more sockets and said two framing members can comprise one or more prongs capable attaching to said one or more sockets. In one embodiment, said one or more sockets can comprise a first socket **410a**, a second socket **410b**, a third socket **410c**, and a fourth socket **410d**. In one embodiment, said one or more prongs can comprise a first prong **412a**, a second prong **412b**, a third prong **412c**, and a fourth prong **412d**. In one embodiment, said second framing member **402b** can comprise a set of said one or more prongs similar to said first framing member **402a**, and said internal assembly **406** can accommodate said one or more prongs of said second framing member **402b**. In one embodiment, attaching said first framing member **402a** to said internal assembly **406** can comprise aligning, inserting and securing said one or more prongs into said one or more socket; wherein, said first socket **410a** corresponds to said first prong **412a**, said second socket **410b** corresponds to said second

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prong **412b**, said third socket **410c** corresponds to said third prong **412c**, and said fourth socket **410d** corresponds to said fourth prong **412d**. In one embodiment, said one or more external rotors can rotate freely around said internal assembly **406** and within a portion of said two framing members.

FIGS. **4C**, **4D** and **4E** illustrate a perspective overview of said second gyroscopic assembly **104b** with a first casing **420**, an elevated front view and an elevated side view of said second gyroscopic assembly **104b** with said first casing **420** and a second casing **422**. In one embodiment, each of said one or more gyroscopic assemblies can comprise a casing assembly. For example, in one embodiment, said second gyroscopic assembly **104b** can comprise said first casing **420** and said second casing **422**. In one embodiment, said first casing **420** can comprise a first clip **421a** and a second clip **421b**, and said second casing **422** can comprise a first clip **423a** and a second clip **423b**. In one embodiment, said casing assembly can comprise an aperture for each of said two prongs of said two framing members. For example, in one embodiment, said apertures can be partially in said first casing **420** and said second casing **422**. In one embodiment, a first case aperture **426** can comprise a first portion **427a** in said first casing **420** and a second portion **427b** in said second casing **422**; wherein, a portion of said first portion **427a** wraps around a portion said first prong **307a** and a portion of said second portion **427b** wraps around a remaining portion of said first prong **307a**. In one embodiment, a similar aperture can be provided at said second prong **307b**.

FIGS. **4F** and **4G** illustrate a perspective top side view of said first clip **421a** and said first clip **423a**, and a perspective bottom side view of said second clip **421b** and said second clip **423b**. In one embodiment, said casing assembly can comprise a clipping system to hold said first casing **420** and said second casing **422** closed comprising said first clip **421a**, said second clip **421b**, said first clip **423a**, and said second clip **423b**. In one embodiment, said first clip **421a** can hold an upper portion of said second casing **422**, said first clip **423a** can hold an upper portion of said first casing **420**, said second clip **421b** can hold a lower portion of said second casing **422**, and said second clip **423b** can hold a portion of said first casing **420**.

FIG. **4H** illustrates said second gyroscopic assembly **104b** on said animal **102** comprising said casing assembly. In one embodiment, said one or more gyroscopic assemblies can each comprise one of said casing assembly. In one embodiment, said one or more gyroscopic assemblies can be designed to comprise an aesthetic similar to other horse training equipment. For example, in one embodiment, said casing assembly can comprise a leather, wood, copper, aluminum or similar material so as to match other training elements used with said animal **102**.

FIGS. **5A**, **5B** and **5C** illustrate a perspective overview and an elevated cross-section front and top view of said second external rotor **403b**. In one embodiment, said one or more external rotors can each have similar specifications to said second external rotor **403b**, with the exception that each can have a unique internal and external diameter. In one embodiment, said second external rotor **403b** can comprise a first side portion **502a**, a second side portion **502b**, and a third side portion **502c**. In one embodiment, a cross-section of said second external rotor **403b** can comprise a squared-U shape with an open end of said squared-U shape facing inward toward a center axis **506** of said second external rotor **403b**. In one embodiment, said second external rotor **403b** can be substantially circular (that is, round) about said third side portion **502c**. In one embodiment, said first side portion **502a** and said second side portion **502b** can be substantially per-

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pendicular to said third side portion **502c**. In one embodiment, said second external rotor **403b** can comprise a plurality of magnets about an inner surface of said squared-U shape. For example, in one embodiment, said first side portion **502a** can comprise a first magnet **504a**, said second side portion **502b** can comprise a second magnet **504b**, and said third side portion **502c** can comprise a third magnet **504c**. In one embodiment, said second external rotor **403b** can rotate about said center axis **506**. In one embodiment, said first external rotor **403a** can comprise a center axis **508**, said second external rotor **403b** can comprise said center axis **506**, and said third external rotor **403c** can comprise a center axis **510**.

FIGS. **5D**, **5E** and **5F** illustrate an elevated top view, an elevated front view, and an elevated side view of said one or more external rotors. In one embodiment, said center axis **508** can be perpendicular to said center axis **510**. In one embodiment, said center axis **506** can be perpendicular to said center axis **510**. In one embodiment, said center axis **506** can be perpendicular to said center axis **508**. Thus, in one embodiment, with said one or more external rotors can be arranged on three axes with said center axis **508** as an x-axis, said center axis **510** as a y-axis, and said center axis **506** as a z-axis. Thus, in one embodiment said one or more external rotors can be arranged in a tri-axial configuration.

FIGS. **6A**, **6B**, **6C** and **6D** illustrate a perspective overview, an elevated top view, an elevated front view, and an elevated side view of one or more internal rails. In one embodiment, said one or more internal rails can correspond to said one or more external rotors and provide an internal track for each of said one or more external rotors to rotate upon. In one embodiment, said one or more internal rails can comprise a first internal rail **602a** having a center axis **604a**, a second internal rail **602b** having a center axis **604b**, and a third internal rail **602c** having a center axis **604c**. In one embodiment, said center axis **604a** can be perpendicular to said center axis **604c**. In one embodiment, said center axis **604b** can be perpendicular to said center axis **604a**. In one embodiment, said center axis **604b** can be perpendicular to said center axis **604c**.

FIGS. **7A**, **7B**, **7C** and **7D** illustrate a perspective first side view, a perspective second side view, an elevated top view and an elevated front view of said third internal rail **602c**. In one embodiment, said third internal rail **602c** (like the others among said one or more internal rails) can comprise a first side **702a**, a second side **702b**, an outer surface **702c**, and an inner surface **702d**. In one embodiment, said third internal rail **602c** can comprise a plurality of magnets. In one embodiment, said plurality of magnets can comprise a first magnet **704a**, a second magnet **704b**, and a third magnet **704c**. In one embodiment, said third internal rail **602c** can comprise a body **706**. In one embodiment, said plurality of magnets can be arranged around a perimeter of said third internal rail **602c**. For example, in one embodiment, said plurality of magnets can be arranged with said first magnet **704a** at said first side **702a**, said second magnet **704b** at said second side **702b**, and said third magnet **704c** around said outer surface **702c**.

FIGS. **8A** and **8B** illustrate a perspective overview of said third internal rail **602c** within a cross-section view of said third external rotor **403c**, and an elevated cross-section view of said third internal rail **602c** and said third external rotor **403c**. In one embodiment, said one or more external rotors can fit around and rotate about said one or more internal rails. In one embodiment, said square-U shape of said one or more external rotors can fit about a portion of said body **706** of said one or more internal rails. In one embodiment, said one or more external rotors will rotate around said one or more internal rails on a magnetic bearing. In one embodiment, said

magnetic bearing can comprise a set of magnetic materials arranged to push said plurality of magnets of said third internal rail **602c** away from said plurality of magnets of said third external rotor **403c**. For example, in one embodiment, said first magnet **704a** can magnetically push away from said first magnet **504a** with a magnetic gap **802a**, said second magnet **704b** can magnetically push away from said second magnet **504b** with a magnetic gap **802b**, and said third magnet **704c** can magnetically push away from said third magnet **504c** with a magnetic gap **802c**.

FIGS. **9A** and **9B** illustrate a perspective overview of a cross-section of said third external rotor **403c** arranged around said third internal rail **602c** and a perspective overview of said one or more gyroscopic assemblies. In one embodiment, said one or more external rotors can rotate about said one or more internal rails. Thus, in one embodiment said one or more external rotors rotating about said one or more internal rails can comprise a three axis gyroscope in three perpendicular planes. In one embodiment, said three axis gyroscope can comprise ball bearings or other more conventional bearings.

FIGS. **10A** and **10B** illustrate said a perspective overview of said internal assembly **406** and said internal assembly **406** with said one or more internal rails. In one embodiment, said internal assembly **406** can comprise a central portion **1002**, one or more legs, and one or more wheels. In one embodiment, said central portion **1002** can comprise one or more batteries (not illustrated). In one embodiment, said one or more wheels can be arranged around an exterior ends of said one or more legs. In one embodiment, said one or more wheels can be used to drive said one or more external rotors (as discussed below). In one embodiment, said one or more wheels can be connected to said one or more batteries (not illustrated) which can be stored in said central portion **1002**. In one embodiment, said one or more wheels can be selectively driven at a variable speed and with a variable duration by a controller (not illustrated). In one embodiment, said one or more legs can comprise a first leg **1004a**, a second leg **1004b**, a third leg **1004c**, a fourth leg **1004d**, a fifth leg **1004e** and a sixth leg **1004f**. In one embodiment, said internal assembly **406** can be arranged to connect said one or more internal rails to one another and to said base portion **205** with said two framing members. In one embodiment, said third internal rail **602c** can attach to said central portion **1002**; said central portion **1002** can attach to said second internal rail **602b** with said first leg **1004a** and said second leg **1004b**; and said central portion **1002** can attach to said first internal rail **602a** with said third leg **1004c**, said fourth leg **1004d**, said fifth leg **1004e** and said sixth leg **1004f**. In one embodiment, said one or more wheels can comprise a first wheel assembly **1006a**, a second wheel assembly **1006b**, a third wheel assembly **1006c**, a fourth wheel assembly **1006d**, a fifth wheel assembly **1006e** and a sixth wheel assembly **1006f**.

FIGS. **10C** and **10D** illustrate said one or more wheels interfacing with said one or more external rotors. In one embodiment, wheel assemblies **1006a-1006f** can each comprise a pair of motor driven wheels mounted to a leg collar. For example, in one embodiment, said first wheel assembly **1006a** can comprise a first wheel **1020a**, a second wheel **1022a**, a leg collar **1024a**, and a first mounting bracket **1026a** and a second mounting bracket **1028a**. In one embodiment, said first wheel **1020a** and said second wheel **1022a** can be driven by an electric motor, steam engine or gas engine (not illustrated but well known in the art). In one embodiment, said gas engine can operate on petrol, propane or similar. In one embodiment, said electric motor can be powered by said one or more batteries in said central portion **1002**. In one embodi-

ment, said leg collar **1024a** can attach to said first leg **1004a**. In one embodiment, said first mounting bracket **1026a** and said second mounting bracket **1028a** can attach to said leg collar **1024a**. In one embodiment, said animal first wheel **1020a** can attach to said first mounting bracket **1026a**, and said second wheel **1022a** can attach to said second mounting bracket **1028a**. In one embodiment, said first wheel assembly **1006a** can hold said first wheel **1020a** and said second wheel **1022a** against said second external rotor **403b**. Likewise, said one or more wheels can be held against said one or more external rotors. In one embodiment, driving said first wheel **1020a** and said second wheel **1022a** can cause said second external rotor **403b** to rotate relative to said second internal rail **602b**.

FIGS. **10D**, **10E** and **10F** illustrate an elevated side view of said third external rotor **403c** with said central portion **1002**; an elevated top view of said central portion **1002** with said second external rotor **403b**, said first leg **1004a** and said second leg **1004b**; and an elevated front view of said central portion **1002** with said third leg **1004c**, fourth leg **1004d**, said fifth leg **1004e**, said sixth leg **1004f** and said first external rotor **403a**. In one embodiment, said one or more wheels can further comprise a ninth wheel assembly **1006i** and a tenth wheel assembly **1006j** (as illustrated in FIGS. **10D** and **10F**). In one embodiment, wheel assemblies **1006g-1006j** can be arranged around said central portion **1002** and press against a portion of said third external rotor **403c**. In one embodiment, said first wheel assembly **1006a** and said second wheel assembly **1006b** can press against a portion of said second external rotor **403b**. And, in one embodiment, said third wheel assembly **1006c**, fourth wheel assembly **1006d**, said fifth wheel assembly **1006e**, and said sixth wheel assembly **1006f** can press against a portion of said first external rotor **403a**. Accordingly, in one embodiment, said one or more wheels can be arranged so as to press against each of said one or more external rotors. In one embodiment, said one or more wheels can be used for driving said one or more external rotors around said one or more internal rails. In one embodiment, said driving of said one or more external rotors can create a set of gyroscopic forces within said second gyroscopic assembly **104b**.

FIGS. **11A** and **11B** illustrate a perspective front overview of said **102**, and a detailed perspective front overview of said first gyroscopic assembly **104a**. In one embodiment, a portion of said animal training system **100** can attach to said head **106** of said animal **102**. In one embodiment, said animal **102** can be trained with a bridle **1102**. In one embodiment, said bridle **1102** can comprise a noseband **1104**, a throat-lash **1106**, one or more reins **1108**, a headpiece **1110**, a brow-band **1112** and a cheek piece **1114**. In one embodiment, said first gyroscopic assembly **104a** can attach to said head **106** of said animal **102** with a gyroscope bracket **1120** attached to a portion of said bridle **1102**. In one embodiment, said gyroscope bracket **1120** can comprise a first anchor **1122** attached to said noseband **1104**, and a second anchor **1124** attached to said throat-lash **1106**. In one embodiment, said gyroscope bracket **1120** can comprise a pair of sockets comprising a first socket **1126a** and a second socket **1126b**. Similar to said gyroscope bracket **204**, said pair of sockets in said gyroscope bracket **1120** can receive a two prongs in said first gyroscopic assembly **104a**.

FIGS. **12A** and **12B** illustrate a perspective overview and perspective top view of said third gyroscopic assembly **104c**. In one embodiment, said third gyroscopic assembly **104c** can attach to said animal **102** with a tail strap assembly **1202**. In one embodiment, said tail strap assembly **1202** can comprise a hook **1204** attached to said seat **124**, a strap **1206** attaching said hook **1204** to a base portion **1208**, and a looping portion

1210 around said tail head 112 of said tail 114 of said animal 102. In one embodiment, said tail strap assembly 1202 can be held in tension between said seat 124 and said tail 114.

In one embodiment, said third gyroscopic assembly 104c can attach to said tail strap assembly 1202 with a gyroscope bracket 1220. In one embodiment, said gyroscope bracket 1220 can attach to said tail strap assembly 1202 at said looping portion 1210. In one embodiment, said gyroscope bracket 1220 can attach at, near or around said tail head 112. In one embodiment, said third gyroscopic assembly 104c can apply a set of gyroscopic forces around said tail head 112 when engaged. In one embodiment, said gyroscope bracket 1220 can comprise a first side portion 1222a, a second side portion 1222b, a central portion 1224, and a pair of sockets. In one embodiment, said pair of sockets can comprise a first socket 1226a and a second socket 1226b. Similar to said gyroscope bracket 204 and said gyroscope bracket 1120, said gyroscope bracket 1220 can comprise a two prongs in said third gyroscopic assembly 104c. In one embodiment, said central portion 1224 can comprise a “U” shape capable of accommodating said third gyroscopic assembly 104c without interfering with its operation.

In one embodiment, said saddle 120 can comprise a battery bag 1230 behind said seat 124. In one embodiment, said battery bag 1230 can comprise a storage area for batteries, or in another embodiment, one or more wires can attach said battery bag 1230 to said one or more gyroscopic assemblies in order to provide a power source to said one or more gyroscopic assemblies from a central location. In one embodiment, storing said batteries at said battery bag 1230 can distribute the weight of said one or more batteries to said back 118 of said animal 102.

In one embodiment, said power source can attach to a one or more engines (not illustrated), said one or more engines can transmit a torque and/or rotation to said one or more external rotor. In one embodiment, said power source can comprise said batteries and said one or more engines can comprise one or more electric motors. In one embodiment, said power source can comprise a gas tank and said one or more engines can comprise one or more internal combustion engines. In one embodiment, said power source can comprise a steam reservoir and said one or more engines can comprise one or more steam engines. Other methods of generating a torque with said one or more engines and said power source are known in the art and are incorporated by reference here.

In one embodiment, said animal training system 100 can comprise a one or more gyroscope brackets capable of attaching said one or more gyroscopic assemblies to said animal 102. In one embodiment, said one or more gyroscope brackets can comprise said gyroscope bracket 204, said gyroscope bracket 1120 and/or said gyroscope bracket 1220.

FIG. 13 illustrates a perspective overview of said animal 102 with an animal training system 1300. In one embodiment, said animal training system 1300 can comprise an alternative embodiment of said one or more gyroscopic assemblies. In one embodiment, said one or more gyroscopic assemblies can comprise a first gyroscopic assembly 1304a, a second gyroscopic assembly 1304b and a third gyroscopic assembly 1304c.

In one embodiment, said animal training system 100 and said animal training system 1300 can comprise a one or more solar panels 1320 on said saddle 120 of said animal 102. In one embodiment, said one or more solar panels 1320 can charge one or more batteries in said battery bag 1230 or provide energy to said one or more gyroscopic assemblies.

FIGS. 14A, 14B, 14C and 14D illustrate a perspective overview of said second gyroscopic assembly 1304b without

a gyroscope bracket 1401, a view with said gyroscope bracket 1401, an elevated side view and an elevated front view with said gyroscope bracket 1401. In one embodiment, said one or more gyroscopic assemblies can be substantially similar to said second gyroscopic assembly 1304b. In one embodiment, said second gyroscopic assembly 1304b, can comprise an upper casing 1402, a lower casing 1404, a first prong 1406a and a second prong 1406b. In one embodiment, said first prong 1406a and said second prong 1406b can comprise a two prongs of said second gyroscopic assembly 1304b. In one embodiment, said gyroscope bracket 1401 can comprise a base 1410, a first side 1412a, a second side 1412b, a first socket 1414a and a second socket 1414b. In one embodiment, said first socket 1414a and said second socket 1414b can comprise a two sockets of said gyroscope bracket 1401. In one embodiment, said second gyroscopic assembly 1304b can mount to said gyroscope bracket 1401. In one embodiment, mounting said second gyroscopic assembly 1304b to said gyroscope bracket 1401 can comprise aligning and attaching said two prongs of said second gyroscopic assembly 1304b to said two sockets of said gyroscope bracket 1401. In one embodiment, said gyroscope bracket 1401 can comprise a “U” shape having said first side 1412a and said second side 1412b as its component sides. In one embodiment, said first socket 1414a can comprise an aperture through a portion of said first side 1412a; likewise, said second socket 1414b can comprise an aperture through a portion of said second socket 1414b. In one embodiment, said base 1410 can attach to a bottom portion of said base 1410. In one embodiment, said base 1410 can comprise an external threading 1411. In one embodiment, said base 1410 can attach to said horn 122. In one embodiment, attaching said 1410 to said horn 122 can comprise screwing said external threading 1411 into said internal threading 210.

In one embodiment, said second gyroscopic assembly 1304b can be substantially planar. In one embodiment, said second gyroscopic assembly 1304b can attach to said gyroscope bracket 1401 at a relative angle 1420 between said base 1410 and said one or more gyroscopic assemblies. In one embodiment, said relative angle 1420 can comprise a perpendicular angle or said relative angle 1420 can be parallel between said base 1410 and said second gyroscopic assembly 1304b. In one embodiment, said relative angle 1420 can be fixed such that said second gyroscopic assembly 1304b does not spin upon said two prongs of said second gyroscopic assembly 1304b.

FIGS. 15A, 15B and 15C illustrate a perspective exploded overview and an elevated front side view of said second gyroscopic assembly 1304b, and a partially assembled perspective overview of said second gyroscopic assembly 1304b without said upper casing 1402. In one embodiment, said second gyroscopic assembly 1304b (or any of said one or more gyroscopic assemblies) can be assembled by aligning its parts on a central axis 1502. In one embodiment, said second gyroscopic assembly 1304b can comprise said upper casing 1402, a first bolt 1504, a gyro disk 1506, a second bolt 1508, a motor 1510, said lower casing 1404, a base 1512, a shaft 1514, a first threading 1516, and a second threading 1518. In one embodiment, said upper casing 1402 can comprise an external threading 1522. In one embodiment, said lower casing 1404 can comprise an internal threading 1520. In one embodiment, said shaft 1514 can align with said central axis 1502 and slide through a portion of each of said upper casing 1402 at an aperture 1526, said first bolt 1504 at an aperture 1527, said gyro disk 1506 at an aperture 1528, said second bolt 1508 at an aperture 1529, and said lower casing 1404 at an aperture 1530. In one embodiment, said second

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bolt **1508** can attach to said first threading **1516**. In one embodiment, said first bolt **1504** can attach to said second threading **1518**. In one embodiment, said gyro disk **1506** can be held between said first bolt **1504** and said second bolt **1508**. In one embodiment, said shaft **1514** can rotate independent of said base **1512**. In one embodiment, said shaft **1514** can rotate freely within a cavity **1540** between said upper casing **1402** and said lower casing **1404**. In one embodiment, said upper casing **1402** can attach to said lower casing **1404** with said external threading **1522** and said internal threading **1520**. In one embodiment, attaching said upper casing **1402** to said lower casing **1404** can comprise screwing said external threading **1522** into said internal threading **1520**. In one embodiment, said second gyroscopic assembly **1304b** need not have said gyro disk **1506** within said upper casing **1402** and said lower casing **1404** to achieve its design goals.

FIGS. **16A** and **16B** illustrate an elevated front view and top view of an animal training system **1600**. In one embodiment, said animal training system **1600** can comprise one or more gyroscopic assemblies comprising a first gyroscopic assembly **1602a**, a second gyroscopic assembly **1602b**, and a third gyroscopic assembly **1602c**. In one embodiment, said saddle **120** can be replaced with a flat saddle **1604**. In one embodiment, said flat saddle **1604** can comprise a flatter top surface than said saddle **120**, it can also lack said horn **122**. In one embodiment, said one or more gyroscopic assemblies can attach to said flat saddle **1604** (illustrated) or said saddle **120** (not illustrated). In one embodiment, said animal training system **1600** can comprise said one or more gyroscopic assemblies oriented in three perpendicular planes. For example, in one embodiment, said first gyroscopic assembly **1602a** can be substantially parallel with said flat saddle **1604**; said second gyroscopic assembly **1602b** and said third gyroscopic assembly **1602c** can be perpendicular to said first gyroscopic assembly **1602a**; and said second gyroscopic assembly **1602b** can be substantially perpendicular to said third gyroscopic assembly **1602c**. In one embodiment, attaching three of said one or more gyroscopic assemblies comprising a single axis to one location on said animal **102** can approximate use of a gyroscopic assembly comprising three axes.

FIGS. **17A** and **17B** illustrate an elevated top view and side view of said animal training system **100** on said animal **102**. In one embodiment, said animal training system **100** can generate one or more angular momentum forces and attach them to said animal **102**. In one embodiment, said one or more angular momentum forces can be utilized in training said animal **102**. In one embodiment, said one or more angular momentum forces can comprise those forces well known in mechanical physics. In one embodiment, said one or more angular momentum forces can comprise forces for maintaining and measuring orientation, based on the principles of angular momentum. In one embodiment, said one or more gyroscopic assemblies of said animal training system **100** can assert said one or more angular momentum forces in three axes (pitch, roll and yaw) which can resist reorientation in three dimensions (as illustrated with inwardly pointing directional arrows). In this sense, it can be said that said animal training system **100** can assert an omnipresent equilibrium orientation on said animal **102**. In one embodiment, said one or more angular momentum forces at said second gyroscopic assembly **104b** approximate a center of mass of a human, as if said human were sitting on said saddle **120**. In one embodiment, said one or more angular momentum forces can be tuned so as to match a training program for said animal **102** and/or a skill of a rider on said animal **102**. For example, in

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one embodiment, tuning said one or more angular momentum forces can comprise increasing or decreasing a speed of said one or more gyroscopic assemblies so as to increase and/or decrease said one or more angular momentum forces. In one embodiment, said one or more angular momentum forces can be used for safety of said rider after a training regime has completed. For example, in one embodiment, said one or more angular momentum forces can calm and steady said animal **102** for riding, working, or pulling tasks.

In one embodiment, said one or more angular momentum forces are capable of intercepting an equilibrium of said animal **102** (that is, a natural equilibrium of said animal **102**) and cause said animal **102** to act in harmony with said one or more angular momentum forces. In one embodiment, said one or more angular momentum forces can break through a natural balance of said animal **102**. In one embodiment, said one or more angular momentum forces are capable of causing said animal **102** to think more carefully about its balance. In one embodiment, said one or more angular momentum forces can be capable of putting said animal **102** out of balance and therefore causing said animal **102** to move in a desired path. In one embodiment, said animal **102** can be said to desire symmetry (that is, said equilibrium of said animal **102**) on all forces acting on itself. For example, if said animal training system **100** put a forward pitch on said animal **102**, said animal **102** may naturally attempt to move in according to said forward pitch and step forward. Thus, in one embodiment said animal training system **100** can be used for directing a movement of said animal **102**.

In one embodiment, said animal training system **100** can be used for stabilization of said animal **102**. For example, in one embodiment, said one or more gyroscopic assemblies can generate said one or more angular momentum forces powerful enough to influence said equilibrium said animal **102** so as to steady the motions of said animal **102**. That is, said animal training system **100** can control a pitch, roll and yaw of said animal **102**. In one embodiment, said animal training system **100** can prevent said animal **102** from rearing back, bucking, jerking, or other undesirable behaviors of said animal **102**. A search of technologies concerning use of one or more of said one or more gyroscopic assemblies to control orientation (or "Control Moment Gyroscopes") will reveal that this concept is in use for control of spacecraft, aircraft and submersible vehicles, but not animals such as said animal **102**.

In another embodiment, said animal training system **100** can be used to keep said animal **102** in a proper state of mind. For example, in one embodiment, where said animal **102** is a horse, said animal **102** can comprise a steady mindset (being safe for human interaction) and a disrupted mindset (being unsafe for human interaction). In one embodiment, said animal training system **100** can steady said animal **102** by applying said one or more angular momentum forces to said body **108** of said animal **102**. For example, in one embodiment, said animal **102** can comprise a known set of gaits (that is, walking patterns); wherein, some gaits are known to indicate said steady mindset and others indicate said disrupted mindset. In one embodiment, said animal training system **100** can be selectively engaged to calm and/or steady said body **108** of said animal **102** so as to maintain or implement said steady mindset. In this way, said animal training system **100** can reinforce and/or correct behavior of said animal **102**. Consequently, said animal training system **100** can facilitate self-control and training.

In one embodiment, said animal **102** can comprise said natural balance which occurs to said animal **102** by instinct. In one embodiment, a method of using said animal training system **100** can comprise breaking through a barrier of said

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natural balance of said animal **102** and (thereby) establishing an independent leadership role for said animal **102**. Accordingly, said animal **102** can gain a self-confidence despite being influenced by said animal training system **100** or a human trainer. That is, said animal **102** can be made to be comfortable relinquishing control of said natural balance of said animal **102**. Thus, in one embodiment said animal training system **100** can be used to establish a training protocol (or an order of authority) and understand the influences of training on himself.

FIGS. **18A** and **18B** illustrate an elevated side view and top view of said animal training system **1300** on said animal **102**. In one embodiment, said one or more gyroscopic assemblies of said animal training system **1300** can comprise said one or more angular momentum forces as applied to said animal **102**. In one embodiment, said one or more gyroscopic assemblies of said animal training system **1300** can each comprise a single axis of rotation and therefore a single axis of said one or more angular momentum forces at each of said one or more gyroscopic assemblies. Accordingly, each of said one or more gyroscopic assemblies can be oriented so as to direct said one or more angular momentum forces as desired. In one embodiment, said one or more gyroscopic assemblies can run at different intensities so as to modify a portion of said one or more angular momentum forces asserted at different parts of said animal **102**. In one embodiment, said second gyroscopic assembly **1304b** can attach to said animal **102** with said gyroscope bracket **1401** or with said horn mount assembly **200**; thus, said one or more angular momentum forces of said second gyroscopic assembly **1304b** can mimic said center of mass of a human (like said second gyroscopic assembly **104b**), as if said human were sitting on said saddle **120**.

FIGS. **19A**, **19B** and **19C** illustrate an elevated side over-view, an elevated detail side view and top view of said animal training system **1600**. In one embodiment, said animal training system **1600** can comprise said one or more angular momentum forces; wherein, said one or more angular momentum forces can be in three axes with one axis each provided by said first gyroscopic assembly **1602a**, said second gyroscopic assembly **1602b**, and said third gyroscopic assembly **1602c**. Accordingly, in one embodiment, said one or more angular momentum forces can originate from one or more of said one or more gyroscopic assemblies attached to said animal **102** at a single location (such as said flat saddle **1604**).

FIG. **20** illustrates a power and control schematic for one of said one or more gyroscopic assemblies. In one embodiment, said one or more gyroscopic assemblies can be provided a power source **2002** from outside of each of said one or more gyroscopic assemblies. For example, in one embodiment, said power source **2002** can comprise said one or more solar panels **1320** and/or said battery bag **1230** (where said one or more gyroscopic assemblies run on electricity), a gas/petrol container (not illustrated) (where said one or more gyroscopic assemblies run on liquid and/or gaseous fuels), or possibly a steam reservoir (where said one or more gyroscopic assemblies run on steam). In one embodiment, said one or more gyroscopic assemblies can be controlled with a controller **2004**. In one embodiment, said controller **2004** can adjust a speed of one or more gyroscopic disks or rings (such as said one or more external rotors or said gyro disk **1506**). In one embodiment, said controller **2004** can disengage said power source **2002** from said one or more gyroscopic assemblies. In one embodiment, said controller **2004** can be controlled by a remote **2006**. In one embodiment, said controller **2004** can control one or more of said one or more external rotors of said second gyroscopic assembly **104b** independent of the others

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among said one or more external rotors. In one embodiment, said power source **2002** can be mounted within said second gyroscopic assembly **104b** (for example at said central portion **1002**, or external to said second gyroscopic assembly **104b** (such as at said battery bag **1230**). In one embodiment, said power source **2002** and/or said controller **2004** can be wired into said second gyroscopic assembly **104b** (or any of said one or more gyroscopic assemblies) through one or more power lines **2008** for said power source **2002** and one or more control lines **2010** for said controller **2004**. In one embodiment, said remote **2006** can communicate with said power source **2002** and/or said controller **2004** wirelessly with a wireless signal **2012** or through a wire connection (not illustrated). In one embodiment, said remote **2006** can control one or more of said one or more gyroscopic assemblies.

Various changes in the details of the illustrated operational methods are possible without departing from the scope of the following claims. Some embodiments may combine the activities described herein as being separate steps. Similarly, one or more of the described steps may be omitted, depending upon the specific operational environment the method is being implemented in. It is to be understood that the above description is intended to be illustrative, and not restrictive. For example, the above-described embodiments may be used in combination with each other. Many other embodiments will be apparent to those of skill in the art upon reviewing the above description. The scope of the invention should, therefore, be determined with reference to the appended claims, along with the full scope of equivalents to which such claims are entitled. In the appended claims, the terms “including” and “in which” are used as the plain-English equivalents of the respective terms “comprising” and “wherein.”

The invention claimed is:

1. An animal training system comprising:
 - an animal harness assembly comprising at least a bridle;
 - one or more gyroscopic assemblies wherein each of said gyroscopic assemblies comprises one or more rotors and a pair of attachment prongs;
 - said one or more rotors each comprise an axis of rotation;
 - one or more gyroscope brackets comprising a pair of sockets for attaching said gyroscope brackets to said one or more gyroscopic assemblies, and a harness fastening member for attaching said gyroscope brackets to said animal harness assembly of an animal;
 - a power source attached to one or more engines;
 - said one or more engines transmit torque to said one or more external rotors;
 - wherein gyroscopic resistance forces are generated through rotation of said one or more external rotors of said one or more gyroscopic assemblies;
 - wherein said gyroscopic resistance forces are selectively applied to alter an equilibrium of said animal;
 - wherein said one or more gyroscope brackets comprise a first gyroscope bracket;
 - wherein said one or more gyroscopic assemblies comprise a first gyroscopic assembly;
 - wherein said first gyroscope bracket is connected to said bridle by said harness fastening member;
 - wherein said first gyroscope bracket attaches said first gyroscopic assembly to said bridle such that gyroscopic resistance forces produced by said first gyroscopic assembly are transferred directly to the head of the animal wearing the harness through said bridle.
2. The animal training system of claim 1,
 - wherein gyroscopic resistance forces provide an omnipresent equilibrium orientation as applied to said animal.

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3. The animal training system of claim 1, wherein said one or more gyroscope brackets further comprise a third gyroscope bracket; said one or more gyroscopic assemblies further comprise a third gyroscopic assembly; said animal harness assembly further comprises a tail strap assembly adapted to selectively attach to a tail of said animal; said third gyroscope bracket attaches to said tail strap assembly; said third gyroscope bracket attaches said third gyroscopic assembly to said animal; and said one or more gyroscopic resistance forces are directed toward a rearward portion of said animal.
4. The animal training system of claim 3 wherein, said one or more gyroscopic resistance forces are directed toward a tail head of said animal.
5. The animal training system of claim 1 further comprising said one or more gyroscope brackets comprise a second gyroscope bracket; said one or more gyroscopic assemblies comprise a second gyroscopic assembly; said second gyroscope bracket attaches to said animal at a saddle; said second gyroscope bracket attaches said second gyroscopic assembly to said animal; and said one or more gyroscopic resistance forces are directed toward a midsection of said animal.
6. The animal training system of claim 5 wherein, said second gyroscope bracket attaches to a horn of said saddle.
7. The animal training system of claim 6 wherein, said second gyroscope bracket comprises a base portion having an external threading selectively attaching said second gyroscope bracket to said horn; and said horn comprises a socket having an internal threading selectively receiving a portion of said base portion of said second gyroscope bracket.
8. The animal training system of claim 1 wherein: said power source comprises one or more batteries; said one or more engines comprise one or more electric motors; and said one or more electric motors propel said one or more external rotors.
9. The animal training system of claim 1 wherein said power source comprises a gas tank; said one or more engines comprise one or more internal combustion engines; and said one or more internal combustion engines propel said one or more rotors.
10. The animal training system of claim 1 wherein: said one or more rotors comprises said one or more external rotors rotating around one or more internal rails on one or more bearings.
11. The animal training system of claim 10 wherein said one or more bearings comprise magnetic bearings.
12. The animal training system of claim 10 wherein said one or more bearings comprise ball bearings.
13. The animal training system of claim 10 wherein said one or more external rotors are arranged in a tri-axial configuration.
14. The animal training system of claim 13 further comprising said one or more external rotors comprise a first external rotor having a center axis, a second external rotor having a center axis, and a third external rotor having a center axis;

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- said one or more internal rails comprises a first internal rail, a second internal rail, and a third internal rail; said first external rotor arranged around said first internal rail; said second external rotor arranged around said second internal rail; said third external rotor arranged around said third internal rail; said center axis of said first external rotor can be perpendicular to said center axis of said third external rotor; said center axis of said third external rotor can be perpendicular to said center axis of said second external rotor; and said center axis of said first external rotor can be perpendicular to said center axis of said second external rotor.
15. The animal training system of claim 1 further comprising said one or more engines are powered in part by one or more solar panels attached to said animal.
16. The animal training system of claim 1 further comprising a casing assembly attached around a portion of said one or more gyroscopic assemblies.
17. The animal training system of claim 1 wherein: said one or more gyroscopic resistance forces are selectively applied to steady a body of said animal so as to maintain or implement a desired gait.
18. The animal training system of claim 1 further comprising said bridle of said animal harness assembly configured to attach to a horse; and wherein said animal harness assembly selectively applies said gyroscopic resistance forces to a horse wearing said animal harness assembly.
19. An animal training method comprising: attaching an animal harness assembly comprising one or more gyroscopic assemblies and a bridle, selectively attaching said animal harness assembly to an animal, wherein each of said one or more gyroscopic assemblies comprising one or more rotors and a pair of attachment prongs; wherein said one or more rotors each comprise an axis of rotation; generating one or more gyroscopic resistance forces with said one or more gyroscopic assemblies by rotating said one or more rotors with one or more engines, and training said animal by selectively applying said one or more gyroscopic resistance forces so as to maintain or implement a desired gait of said animal; wherein said one or more gyroscope brackets comprising a pair of sockets for attaching said gyroscope brackets to said one or more gyroscopic assemblies, and a harness fastening member for attaching said gyroscope brackets to said animal harness assembly of an animal; wherein said animal harness assembly further comprising a power source attached to said one or more engines; wherein said one or more engines transmit torque to said one or more rotors; wherein gyroscopic resistance forces are generated through rotation of said one or more rotors of said one or more gyroscopic assemblies; wherein said one or more gyroscope brackets comprise a first gyroscope bracket; wherein said one or more gyroscopic assemblies comprise a first gyroscopic assembly; wherein said first gyroscope bracket is connected to said bridle by said harness fastening member;

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wherein said first gyroscope bracket attaches said first gyroscopic assembly to said bridle such that gyroscopic resistance forces produced by said first gyroscopic assembly are transferred directly to the head of the animal wearing the harness through said bridle.

20. The animal training method of claim 19 wherein, training said animal comprises:

stabilizing said animal with said one or more gyroscopic resistance forces generated by said one or more gyroscopic assemblies.

21. The animal training method of claim 20 further comprising applying an omnipresent equilibrium orientation to said animal; wherein,

said one or more gyroscopic assemblies comprise tri-axial gyroscopes.

22. The animal training method of claim 19 wherein, training said animal comprises:

applying said one or more gyroscopic resistance forces and putting said animal out of balance.

23. The animal training method of claim 19 wherein, training said animal comprises:

applying said one or more gyroscopic resistance forces and putting said animal out of balance; and establishing a leadership role for said animal with said one or more gyroscopic assemblies.

24. The animal training method of claim 19 wherein, training said animal comprises:

directing a movement of said animal by:
 applying said one or more gyroscopic resistance forces and
 putting said animal out of balance in a direction of a desired path.

25. The animal training method of claim 19 further comprising:

applying said one or more gyroscopic resistance forces to one or more portions of a body of said animal.

26. The animal training method of claim 25 further comprising:

simulating a center of mass of a human by placing one or more of said one or more gyroscopic assemblies above a midsection of said body of said animal.

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27. An animal training system comprising:

an animal harness assembly comprising at least a saddle; one or more gyroscopic assemblies wherein each of said gyroscopic assemblies comprises one or more rotors and a pair of attachment prongs;

said one or more rotors each comprise an axis of rotation; one or more gyroscope brackets comprising a pair of sockets for attaching said gyroscope brackets to said one or more gyroscopic assemblies, and a harness fastening member for attaching said gyroscope brackets to said animal harness assembly of an animal;

a power source attached to one or more engines; said one or more engines transmit torque to said one or more rotors;

wherein gyroscopic resistance forces are generated through rotation of said one or more rotors of said one or more gyroscopic assemblies;

wherein said gyroscopic resistance forces are selectively applied to alter an equilibrium of said animal;

wherein said one or more gyroscope brackets comprises a first gyroscope bracket;

wherein said one or more gyroscopic assemblies comprises a first gyroscopic assembly;

wherein said first gyroscope bracket is connected to said saddle by said harness fastening member;

wherein said first gyroscope bracket attaches said first gyroscopic assembly to a horn of said saddle such that gyroscopic resistance forces produced by said first gyroscopic assembly are transferred directly to the midsection of the animal wearing the harness through said saddle.

28. The animal training system of claim 27 wherein, said first gyroscope bracket comprises a base portion having an external threading selectively attaching said first gyroscope bracket to said horn; and said horn comprises a socket having an internal threading selectively receiving a portion of said base portion of said first gyroscope bracket.

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