1DoF and 6DoF Resume feature

The aim is to pause and resume the motions of the 1DoF, 6DoF and combined system.

# 1DoF feature:

* User clicks on “Stop motion” -> Boolean “motionPlay1D” turns false
* TheSendVoltageValues loops on the input calculated values and send voltage values to the Arduino Board each 200ms.
* For each iteration, condition if “motionPlay1D” is equal to false, save the index in a static variable, then loop stops and “Stop1DPlatform” is called at the same time. This function sends “Stop” to serialPort and stops the platform by sending 0 Left and Right PWM until the next data is sent.
* The function “Resume1DRobot” is based on the “Run1DRobot” feature. This function starts a thread and call the function “resumeMotion1D” which calls sendVoltageValues with sliced velocityValues (starting from the index saved)

# 6DoF feature:

* User clicks on “Stop motion”-, Boolean “motionPlay” turns true
* “resetRun” function is called and sends “stop” to the controller and clear all plots. The robot controller interprets the message and stops the 6DoF platform.
* Get the last position and timestamp recorded in real time by robot feedback (“monitorData” function) and make the robot start by this position. The new input list the sliced original input file. Calculate the travel time from the actual stopped position of the robot and the next timestamp (first position of the new list). Delay the plotting function (“through monitorData”function) by this travelling time.