* Showing the body index and body in a same screen.
* Connecting the
  + Elbow-wrist vector
  + Shoulder-elbow vector
  + Ground normal vector
    - To get the rotation matrix M
* Connect the Bluetooth to the C++.
  + Get the acceleration A(ax, ay, az)
* Correct the acceleration by A’ = A – Mg
* Also provides the correct quaternion when available
* So the actual workflow
  + If Kinect available 🡺 provides absolute quaternion to nullify gravity.
  + If Kinect not available 🡺 use acceleration to complimentary filter the angle quaternion.