Architecture: Technology stack per abstraction level

			Joint movement			UART
AL4: Kinematics/UI			Movelt (GUI)			Control listener
			HMI (Text terminal)			Serial comms
Al 2: Control	Global	I2C		ADC	CAN	
AL3: Control			Main loop			
	State machine	Update IMU reading	update joint controller	update current meas.	CAN executives	
	Calibration		update encoder count			
AL2: Drivers						String cmd
ALL: BIWEIS						parser
						ROS parser
		Accelerometer driver	Motor driver	ADC driver	CAN driver	UART driver
AL1: Peripherals-						
	gpio	i2c	tim	adc	can	usart
	unit config		interrupts			