1. [pi\_lgr\_base, baseQR] = base\_params\_qr(includeMotorDynamics)
   1. 回归的总参数：ixx(i),ixy(i),ixz(i),iyy(i),iyz(i),izz(i),hx(i),hy(i),hz(i),m(i)
   2. 寻找基本参数
      1. 计算包含25条轨迹的观测矩阵W
      2. 对W进行QR分解：

% R is upper triangular matrix

% Q is unitary matrix

% E is permutation matrix

[Q, R, E] = qr(W);

* + 1. 确定独立和非独立参数，计算基本参数pi\_lgr\_base
    2. 保存QR分解的结果：
       1. baseQR.numberOfBaseParameters：基本变量的个数
       2. baseQR.permutationMatrix：E
       3. baseQR.beta = beta;
       4. baseQR.motorDynamicsIncluded = includeMotorDynamics;是否有电机
  1. [Tau, Wb] = buildObservationMatrices(idntfcnTrjctry, baseQR, drvGains)
     1. 得到观测矩阵：WB；力矩：Tau
  2. [sol.pi\_b, sol.pi\_fr, sol.pi\_s] = physicallyConsistentEstimation(Tau, Wb, baseQR);