Plan

* **Update to MuJoCo 200**

(faster simulation, better support for soft body, parallel computation)

1. Openloop training
2. System identification
3. GUI, testing and analysis

* **Try D2C on Dbar**

1. State space definition
2. Position actuator

* **Tensegrity fish**

1. Minimum mass fish tensegrity model
2. Implement D2C
3. Analyze kinetics
4. Take advantage of accurate model dynamics and think of more control method
5. Build a real fish robot and test the control performance