20210415

* The yaw angle return to zero logic need to be added
* The load cell, potentiometer and IMU need to be calibrated, spring stiffness also need to be calibrated
* System parameter and motor + driver actuation unit parameter calibration

20210521

* High-level controller end condition
* The time-up stop condition for timer-loop need to be determined
* Initialization logic for Ready signal receiving √
* Sensor feedback showing in MATLAB √
* Stop commanded in MATLAB √
* High-level and low-level handshake process √

20210526

* The phase index calculation function
* The 'mode' meaning should be adjusted along with the UID strategy
* High-level controller stop process determination
* Stop command send for low-level controller
* Make sure the low-level controller received the stop command

20210610

* The friction coefficients and offset of the Bowden-Cable transmission
* Visually and experimentally check the initial position of left & right support beam need to be as close and symmetric as possible for better triangular configuration matching
* Experimentally check the initial value and varying direction of each sensor.