Before actuate the prototype:

Sensor Calibration 🡪 Sensor Initial Value Calibration 🡪 Sensor Feedback Process and Uploaded Info Package Checking 🡪 Power Supply Checking 🡪 MCU Electrical Cable Connection Checking 🡪 Motor Operation Direction Checking 🡪 The Following Checking Terms Mentioned in Test Conclusion.docx and Test Reminder.docx

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* 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

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* 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 √

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* The phase index calculation function
* Should make sure the phase index and torque feedback is consistent and coincides to the practical scenario
* 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 √

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* 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.

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* Check the limitation setting of control related value
* Total Ta
* Delta Ta
* P components
* Every kinds of compensation term