20210420

* Check if every information from sensor and corresponding calculation is correct before implement controller
* High-level logic and thresholds are waited to be checked and determined

20210421

* Record expected initial value of every sensor

20210813

* The hip joint velocity feedback is very essential, so the velocity feedback may be obtained from motor driver or potentiometer feedback differentiation. Should be selected

20210901

* The restriction of total control command is better to restrict for different status like TM(Walking etc.) or AM(Bending) with different constraints like average human motion compensation value for M and a small value for AM
* Like the HCHP version prototype, the PID control parameters should be reset during certain statuses

20210908

* Record the MCU program running frequency for low-pass filter sampling rate setting