This contains several iterations of the code, listed in alphabetical order, with the most correct version labeled as ‘Final\_Version.ipynb’. These are jupyter notebooks, for ease of use, but can be easily converted to .py simply by taking their contents and removing excess formatting.

This code accepts two files: one containing the calculated angles to the source and the other containing the matching robot positions.

* The angular data is expected to be in the form that ‘Position\_finder.py’ is currently in. Should a more sensible coordinate system be used, the converter can be altered or entirely removed as needed.