Goal: To code swarm robotics (Much more simpler than it sounds) garbage drones

There are four drones that operate on a clock:

1. The ground trash bin drone: Is a drone that rolls around carrying the trash bin under the drones.
2. The two arm plastic bag drone: Is a drone that hovers for approximately 10 minutes per round and picks up trash. Or one arm -> trash drone
3. Robot Arm codes: Computer vision feedback loop that detects trash on the floor, most likely imported from another machine learning library that detects trash we are yet to find.
4. Basic charger port: This charger port is connected to a wall charger most of the time, or maybe with Amazon Alexa’s IoT compartment/software. If outside, then solar charges. Has a circuit breaker, and 3 charger ports that load electricity into the three drones.

* In the middle of the night, or at the end of each cleaning shift, the robots go back to the charger port.
* Coding languages used for machine learning in robotic arms:

Python, Matlab, Ruby

* Coding languages used for machine learning in Arduino ports:

C++, C#, C, Verilog, C+

* Uses raspberry pi too

Robotic arm Python packages:

* xARM
* ROS
* Side note: Do not let it bump into cars and people.