Leg control using a Pypot

The aim of this TP is to use the pypot library to communicate with the motors.

1. Be sure to have pypot properly installed (http://poppy-project.github.io/pypot/installation.html)
2. Test (and understand) the example program
3. Change the motors positions to 10°, 20° and 30°
4. Write a loop to make the motors follow a sinusoid of frequency 0.5Hz and amplitude 10° centered at 0°. You need to use numpy.sin(), numpy.pi and time.time()
5. Write a generic function to change a motor id and change the ids of your motors to 10,11,12.

NOTE:

Everything you need to use in pypot is documented here: http://poppy-project.github.io/pypot/pypot.dynamixel.html#module-pypot.dynamixel.io