Sprint 4 Planning

- Getting the robot arm to move via (Ethernet) using TwinCAT: (Dimitar, Luuk)
- Sending and receiving the correct commands using ADS: (Rik, Jorn)
- Connecting Unity to the PLC and the PLC to the robot arm: (Rik, Dimitar, Luuk, Jorn)
- Document all programs for next group(s): (Rik, Dimitar, Luuk, Jorn)
- Add comments to code in all programs for next group(s): (Rik, Dimitar, Luuk, Jorn)
- Refactor/clean file structure: (Rik, Dimitar, Luuk, Jorn)