Aspects

- Evaluation system

- Collision Detection system

- obtain contact points and match to find which objects the collisions happened between (completed)

- score system providing rewards throughout the episode vs at the end of episode

- ‘debouncing’ so not penalised for contact which occurs over several time steps. Using dictionary of switches to decide if this is a ‘new’ contact or not ( maybe this is not necessary to really discourage touching blocks of the wrong color?)

- Environment class

- figuring out comms between supervisor and robots.

- RL algorithm Implementation