Parameters can be modified

Functions

- changeDynamics (Body ID, Link ID, optionals)
  - optionals:
    - mass
    - lateral friction on contact
    - spinning friction on contact
    - Rolling friction on contact
    - Restitution | bouncyness on contact ???
    - linearDamping of the link (by default 0.04)
    - angularDamping of the link (by default 0.04)
    - contactStiffenss
    - contactDamping
    - frictionAnchor ????
    - localInertiaDiagonal (It'sconsidered in the center of mass an don't have out of diagonal elements)
    - anisotropicFriction
    - jointDamping (it should be close to 0)
    - maxJointVelocity (Default 100 units)
- setJointMotorControl2
  - Maximum force
  - Maximum vel
- Modify In urdf
  - mass link
  - inertia link
  - damping joints
  - friction joints
  - lower limit joint
  - upper limit joint
  - effort joint
  - velocity joint

Functions to do tests

saveState (To save the initial state)

restoreState (int stateID) , to modify the state to the saved one