List of possible bugs detected in Morse Simulator

Simulation and communications management in a multi-robot environment

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List of possible bugs detected

1. The robot **Jido()** doesn't fall with gravity:

   jido.translate(x=-5, z=1).... It is levitating all the time with this 'z' coordinate.

2. Documentation of **Supervision Services** doesn't present all methods like *get_all_stream_ports*.
   http://www.openrobots.org/morse/doc/latest/user/supervision_services.html

3. Class **Quadrotor()**, 2 different robots with the same name? The 2nd is the default (?)

   http://www.openrobots.org/morse/doc/latest/user/robots/quadrotor.html

   http://www.openrobots.org/morse/doc/latest/user/robots/quadrotor_dynamic.html