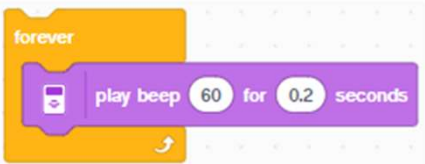


# PYTHON EV3 CODING TIDBITS

1

## BEEP

 = `ev3.speaker.beep()`

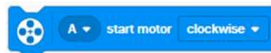
 = 

```
while True:  
--TAB--ev3.speaker.beep()
```

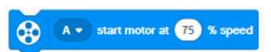
2

## Single motor driving

```
motorR = Motor(Port.C)
```

 = `motorR.run(300)` # (For counterclockwise use -300)

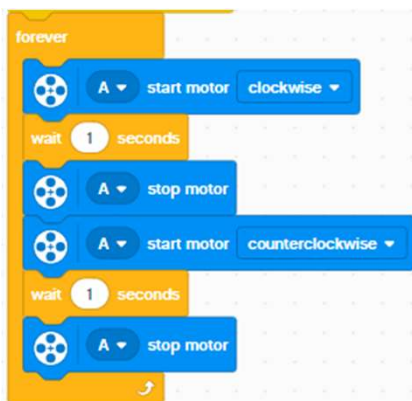
 = `motorR.stop()`

 = `motorR.run(225)`

 = `motorR.run(300)`  
`wait(1700)`

3

## EXAMPLE:



```

While True:
  --TAB-- Motor.run(300)
  --TAB-- wait(1000)
  --TAB-- Motor.stop
=
  --TAB-- Motor.run(-300)
  --TAB-- wait(1000)
  --TAB-- Motor.stop
  
```

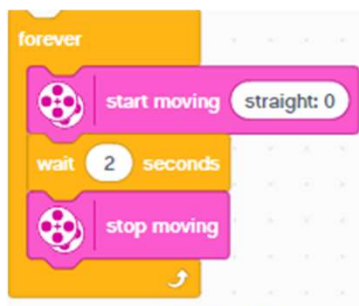
4

# Robot driving

	<code>robot = DriveBase(MotorL, MotorR, 55.5, 104)</code>
	<code>= robot.drive(300, 0)</code> <code>wait(1700)</code>
	<code>= robot.drive(200, 0)</code>
	<code>= robot.stop()</code>
	<code>= robot.drive(150, 0)</code>
	<code>= robot.drive(150, 0)</code> <code>wait(850)</code>

5

## EXAMPLE:







=

```
While True:
--TAB--robot.drive(300, 0)
--TAB--wait(2000)
--TAB--robot.stop()
```

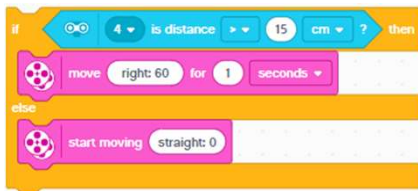
6

## Control

	=	<code>wait(1000)</code>	
	=	<code>if &lt;SOMECONDITION&gt; :</code> <code>--TAB--#someCode</code> <code>else:</code> <code>--TAB--#someCode</code>	
	=	<code>while True:</code> <code>--TAB--#someCode</code>	
	=	<code>while &lt;SOMECONDITION&gt;:</code> <code>--TAB--wait(1)</code>	(make sure to check for something that IS NOT TRUE)

7

## EXAMPLE:



```






if (sensorname).distance() > 150:
--TAB--robot.drive (300, 60)
else:
--TAB--robot.drive (300, 0)
wait(1000)

```

8

# Sensors

```
color_sensor = ColorSensor(Port.S3)
```

	=>	<code>color_sensor.reflection() &lt; 50</code>
	=>	<code>color_sensor.color () = red</code>
	=>	<code>color_sensor.pressed = (true or false)</code>
	=>	<code>color_sensor.distance() &lt; 150</code> <i>(in python distance is measured in MM)</i>
	=>	<code>color_sensor.angle() &lt; 45</code>