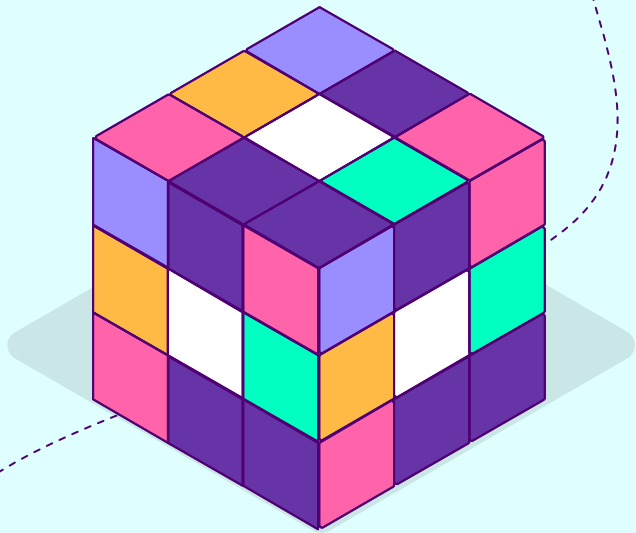


# Visual Programming in JupyterLab with **Blockly**





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QuantStack  
Scientific Computing

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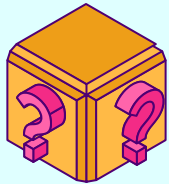
## Robotics Applications

Live demo for JupyterLab-Niryo & JupyterLab-Lego-Boost

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# Visual Programming

*Programming without having to  
deal with specific syntax*



Learn fundamental  
programming concepts  
faster



Important part of early  
computer science education

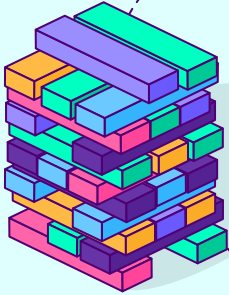


Provide a smoother ramp for  
learners in the Jupyter  
ecosystem



Great tool for robotics  
prototyping

# JupyterLab-Blockly



A JupyterLab extension that uses **interlocking graphical blocks** to represent coding concepts, while giving the user full creative freedom, it removes all language specific syntax requirements.



An open source library designed by Google to make coding easier and more accessible through block-based visual programming.

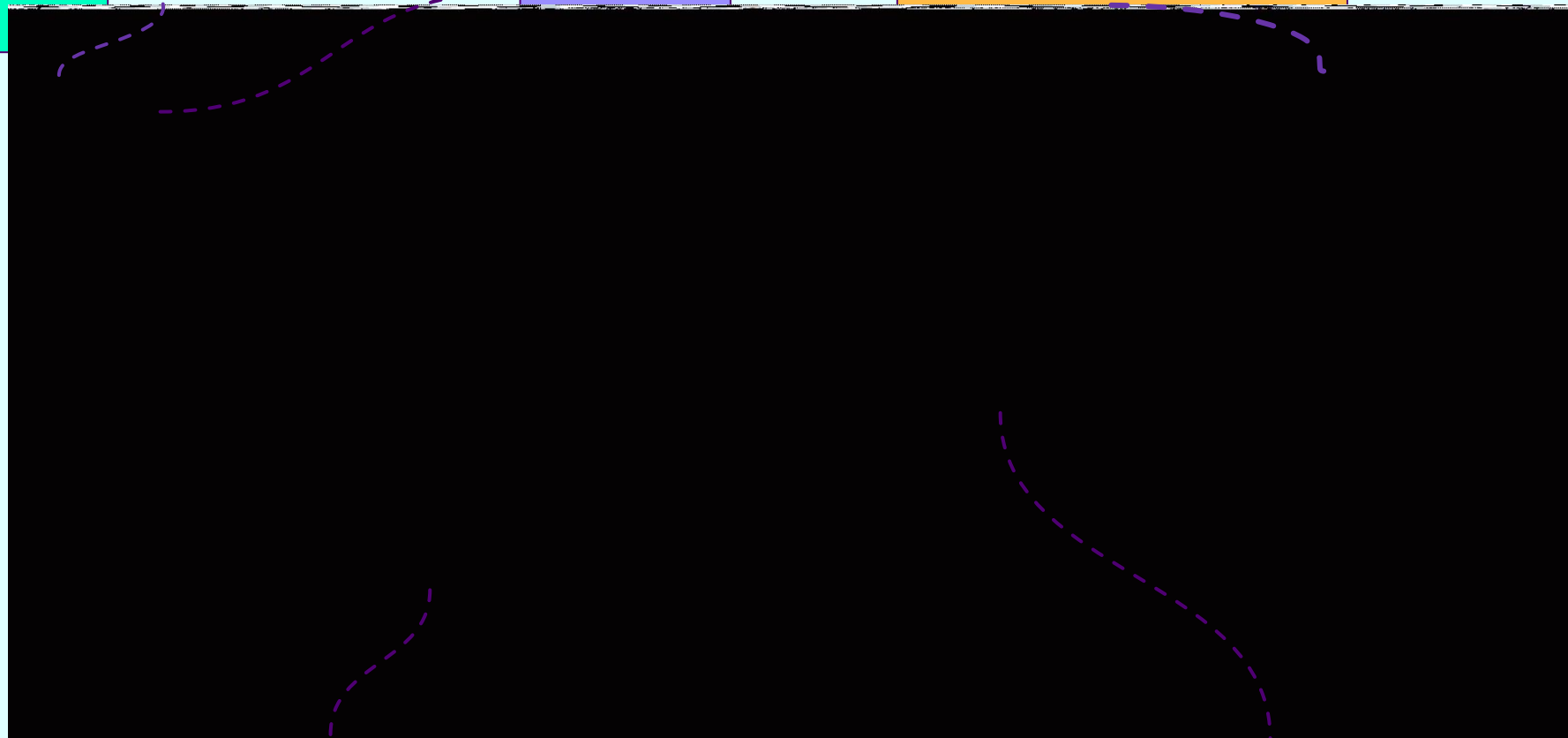
Run

Toolbox

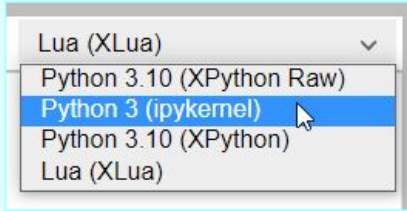
Switch toolbox or kernel

Code & Output

Workspace

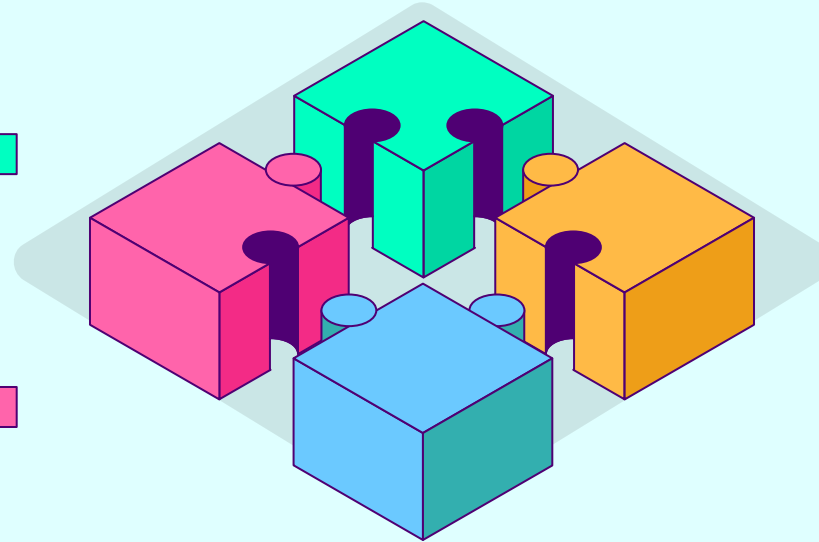
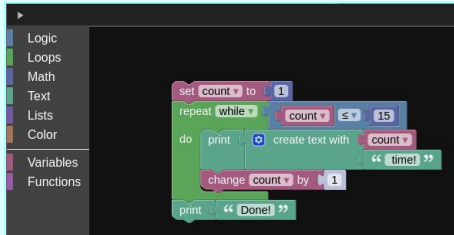


# Smooth Jupyter Integration

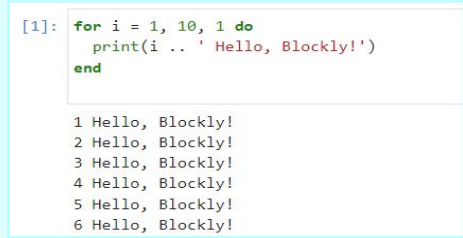


Use **Jupyter kernels** to execute the generated code

Modify its colors based on your individual **theme** (dark, light or personalized)

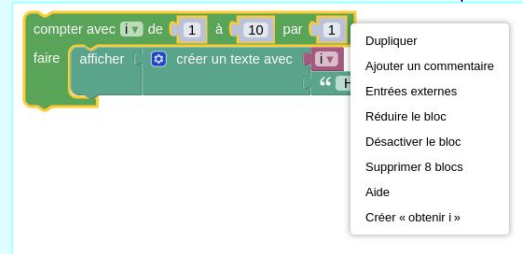


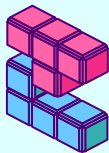
```
mamba install -c conda-forge jupyterlab-blockly
```



Reuse the JupyterLab **code cell** component to display the generated code

Support **translations and localization** (blocks and workspace)





# STEP BY STEP

## how to build on top of JupyterLab-Blockly

cookiecutter <https://github.com/jupyterlab/extension-cookiecutter-ts>

Create JL extension  
from template

01

02

03

04

05

06

Register new blocks,  
toolboxes, generators

Additional  
configurations

Import  
JupyterLab-Blockly

```
j!pm add jupyterlab-blockly
```

```
import { IBlocklyRegistry } from 'jupyterlab-blockly';
```

```
// setup.py : 57
setup_args = dict(
    ...
    install_requires=['jupyterlab-blockly>=0.1.1,<0.2']
    ...
)
```

Include patches

```
// patches/@jupyterlab+codeeditor+3.4.3.patch
diff --git a/node_modules/@jupyterlab/codeeditor/lib/editor.d
index ffe8d1f..d63b2f8 100644
--- a/node_modules/@jupyterlab/codeeditor/lib/editor.d.ts
+++ b/node_modules/@jupyterlab/codeeditor/lib/editor.d.ts
@@ -44,7 +44,7 @@ export declare namespace CodeEditor {
    /**
     * An interface describing editor state coordinates.
     */
    interface ICoordinate extends JSONObject, ClientRect {
    }
    /**
     * A range.
     */
}
```

Extra! Use conda to  
package the extension for  
easier installation



# Importing the `IBlocklyRegistry`

The class that the JupyterLab-Blockly extension exposes to other plugins, it allows other plugins to register new Toolboxes, Blocks and Generators that users can use in the Blockly editor.

```
registerBlocks(blocks: JSONObject[]): void {  
    Blockly.defineBlocksWithJsonArray(blocks);  
}
```

```
registerToolbox(name: string, value: JSONObject): void {  
    this._toolboxes.set(name, value);  
}
```

```
registerGenerator(name: string, generator: Blockly.Generator): void {  
    this._generators.set(name, generator);  
}
```

01

## Register Blocks

Using their JSON definition and generator code in all supported programming languages

02

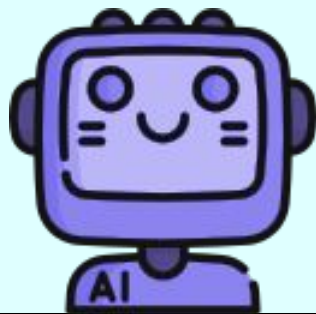
## Register Toolboxes

Once registered, the toolbox will appear automatically in your Blockly editor

03

## Register Generators

Once registered you can easily switch to it in the Blockly editor



Now that you saw how to build on top of **JupyterLab-Blockly**, let's take a look at the robotics applications we created!

# JupyterLab-Niryo-One



The screenshot displays the JupyterLab environment. On the left, the 'niryo' extension is installed, showing a sidebar with categories: Logic, Loops, Math, Text, Lists, Color, Variables, and Functions. Under the 'Functions' category, the 'Niryo Connect' toolbox is expanded, revealing blocks for 'Niryo Movement', 'Niryo Trajectory', 'Niryo Frames', 'Niryo IO', 'Niryo Tools', 'Niryo Vision', 'Niryo Conveyors', 'Niryo Sounds', and 'Niryo Led Ring'. A specific sequence of blocks is shown: 'IP Address' (169, 254, 200, 200), 'Calibrate motors (auto)', 'Move Joints' (j1: 0, j2: 0, j3: 0, j4: 0, j5: 0, j6: 0), 'Wait for' (2 seconds), and 'Move to home pose'. Below this, a code cell shows the Python code for the 'Niryo Connect' class.

```
[6]: from pyniryo import *  
  
class niryo_connect():  
    def __init__(self, ip):  
        self.n = NiryoRobot(ip)  
    def __enter__(self):  
        return self.n  
    def __exit__(self, exception_type, exception_value, traceback):  
        self.n.close_connection()
```

On the right, the 'Zethus' window shows a 3D simulation of a blue 6-axis robotic arm in a virtual environment. The interface includes a 'Controls' button and a 'Pose Estimate' button. The status bar at the bottom indicates 'RQT Graph' and 'Raw: ☐ Expand'.

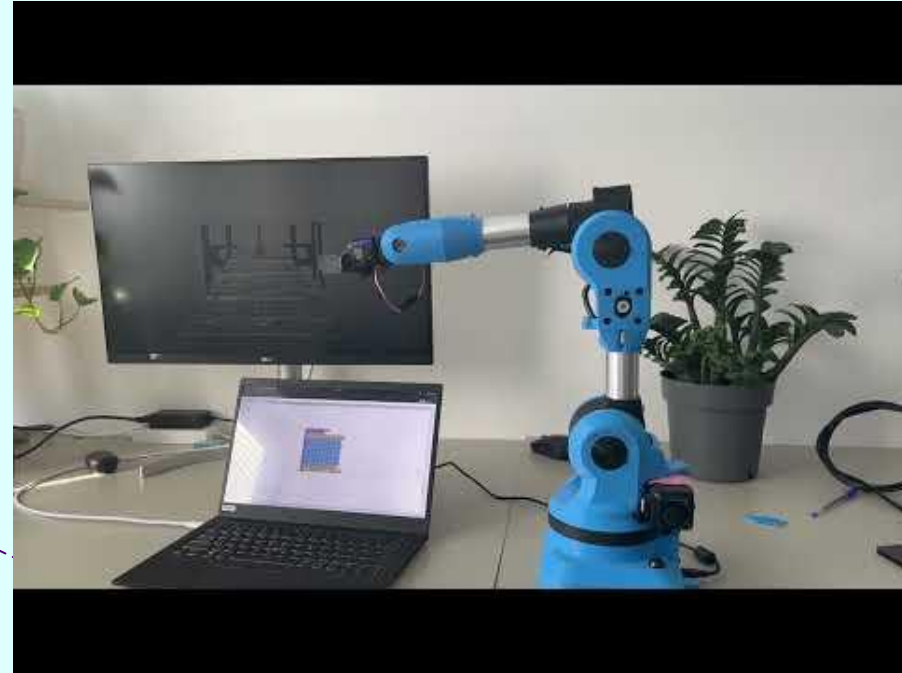
The extension offers two toolboxes and full compatibility to the Niryo One, Ned and Ned2 robots.

Each toolbox contains 130 blocks, organized in 10 categories.

The blocks generate Python code, using the functions from the *pyniryo* API.

Niryo builds 6-axis robots made for higher education, vocational training and R&D laboratories, particularly adapted to study robotics and programming in the context of the industry 4.0.

# JupyterLab-Niryo-One



# JupyterLab-Lego-Boost

Live Demo!

Say hi to Vernie!



Communicate with the MoveHub (a bluetooth hardware piece)



Pass commands through Bluetooth Low Energy (BLE) wireless protocol



Use blocks which generate Python code with the use of the *pylgbst* library

```
from pylgbst.hub import MoveHub
from pylgbst import get_connection_bleak

import time
conn = get_connection_bleak(hub_mac='00:16:53:C3:C2:4F', hub_name=MoveHub.DEFAULT_NAME)
hub = MoveHub(conn)
hub.motor_AB.timed(0.7, 0.6, 0.6)
hub.motor_A.timed(0.4, 0.6)
hub.motor_AB.timed(0.5, (-0.8), (-0.8))
hub.motor_B.timed(0.3, 0.6)
hub.motor_AB.timed(0.4, 0.6, 0.6)
hub.motor_external.stop()
hub.disconnect()
```

Connect to MoveHub on address

Move group motors AB for time  and speeds for motor A  and B

Move motor A for time  and speed

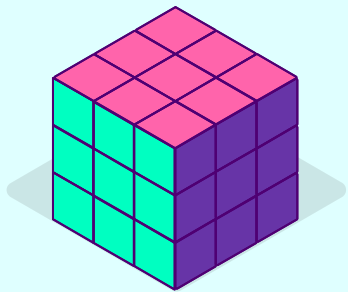
Move group motors AB for time  and speeds for motor A  and B

Move motor B for time  and speed

Move group motors AB for time  and speeds for motor A  and B

Stop motors

Disconnect from MoveHub



All source code can be found  
on the **QuantStack Github** page  
- feel free to give it a try and let  
us know what you think!

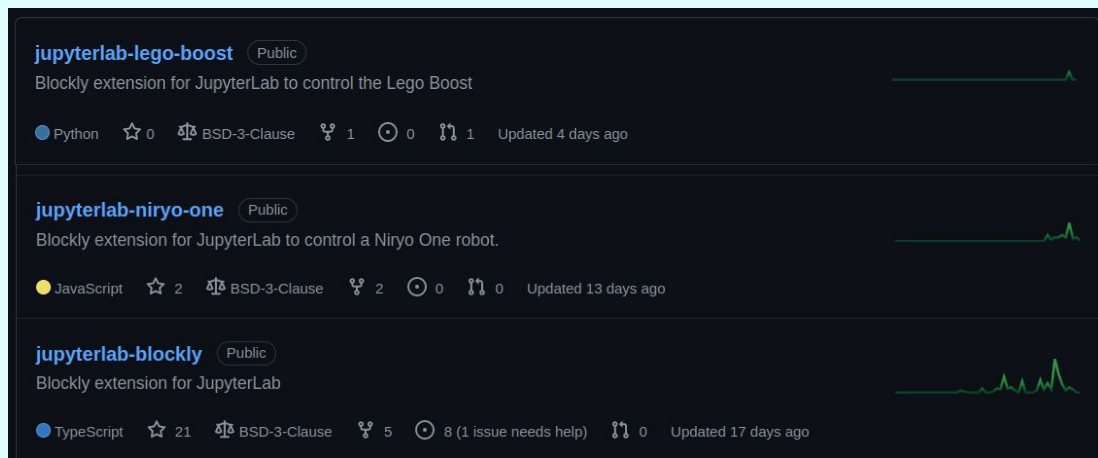
A special thank you to  
**Carlos Herrero!**



hbcarlos



carlosherrerob



# THANK YOU!

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Scientific Computing

