# eBot API

## General

**connect()**: Connects to the (first) eBot the computer is connected to

**close()**: Close the comport

**halt()**: Halts the eBot, turns motors and LED off

## Outputs

**led(bool):** Turns led on, if input is 1, off if input is 0

**wheels(Ls,Rs)**: Controls the wheel speed using specified values

**buzzer(frequency, time):** Plays the buzzer for given time at given frequency

## Sensors

**robot_uS()**: Returns a tupple containing all ultraSonic readings

**light()**: Returns a tupple containing LDR readings from as 0 to 1, 1 being brightest

**obstacle()**: Reads the obstacle in front of the front sonar sensor

Returns true if the vale is less than 250 mm

**acceleration()**: Returns the absolute value of the X,Y, theta coordinates of the robot with reference to starting position

## Example

```
From eBot import *

From time import *

eBot = eBot()

eBot.connect()

eBot.wheels(1,1) full forward

sleep(1)

eBot.wheels(0,0) Stop - can use halt as well

sleep(0.5)

eBot.led(1)

eBot.wheels(-1,-1) full backward

sleep(1)

eBot.halt()
```