

## 04. Servo control (PTZ control)

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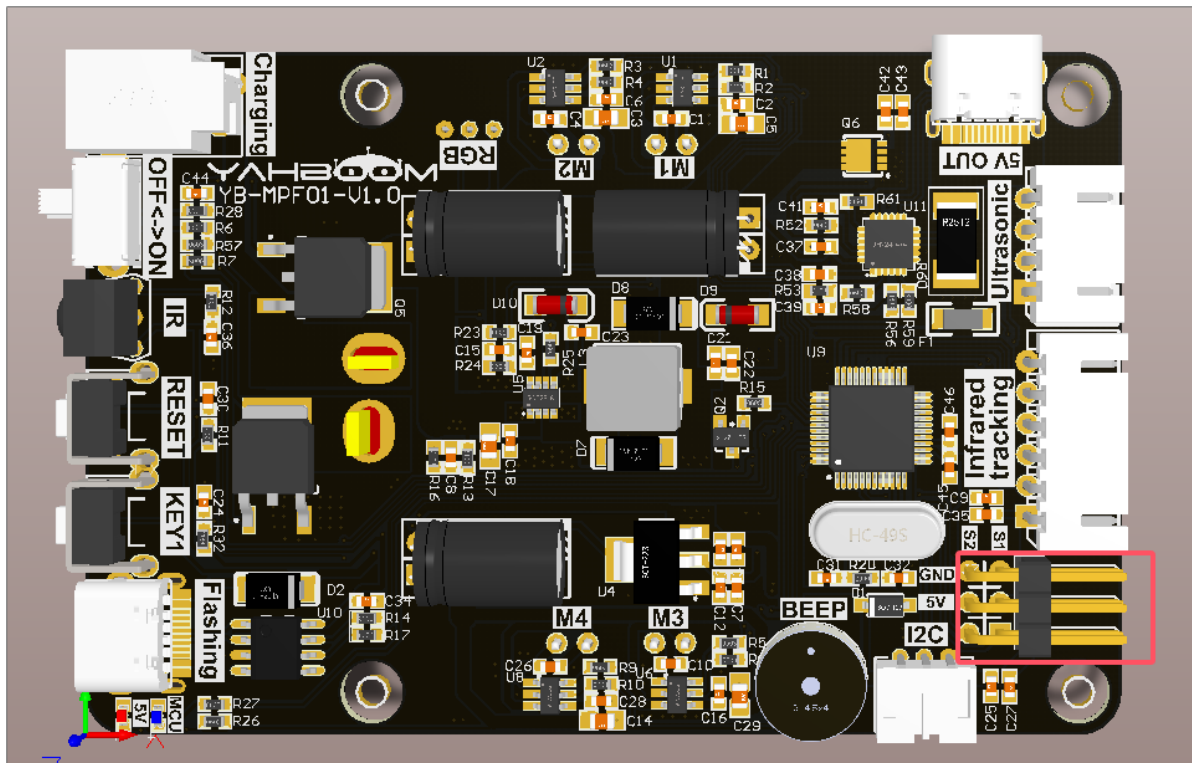
1. Learning objectives
2. Experimental preparation
3. Core code analysis
4. Experimental phenomenon

### 1. Learning objectives

Control the servo connected to the expansion board.

### 2. Experimental preparation

As shown in the figure below, connect the servo to the interface.



### 3. Core code analysis

Raspbot\_Lib library functions needed to control the servo:

```
ctrl_servo(id, angle):
```

Parameter explanation: Control connected to expansion board S1, S2.

id=1: Control S1 servo, id=2: Control S1 servo.

angle=[0,180], control the rotation angle of the servo

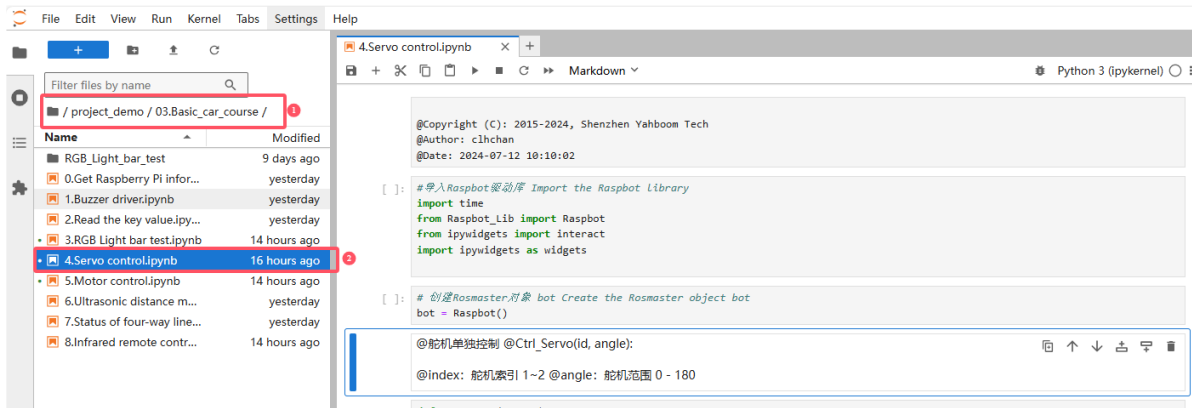
Return value: None.

Source code path: project\_demo\03.Basic\_car\_course

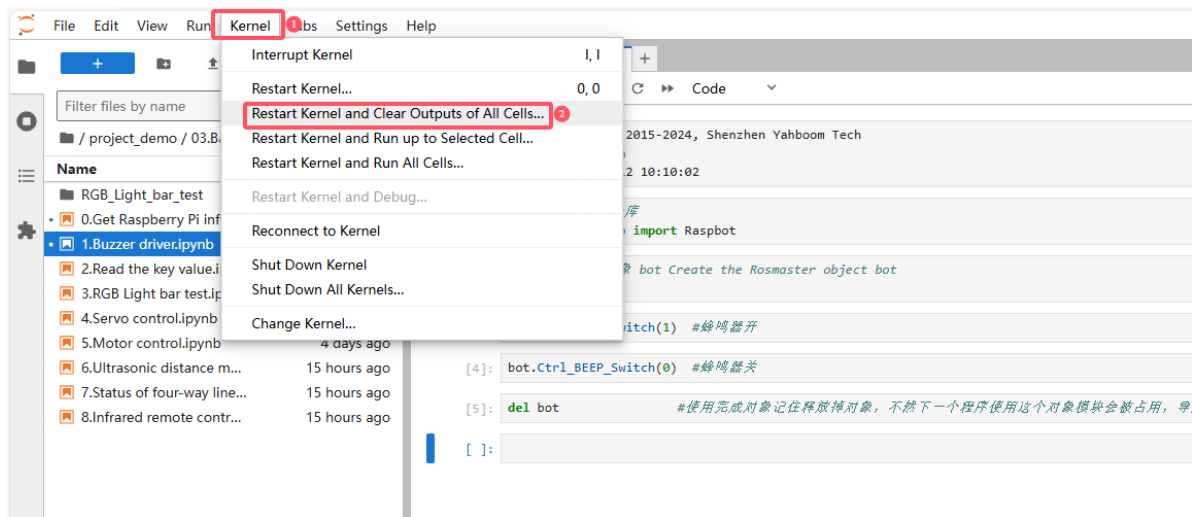
## 4. Experimental phenomenon

Turn on the robot, open the computer browser to enter the Jupyter lab editor

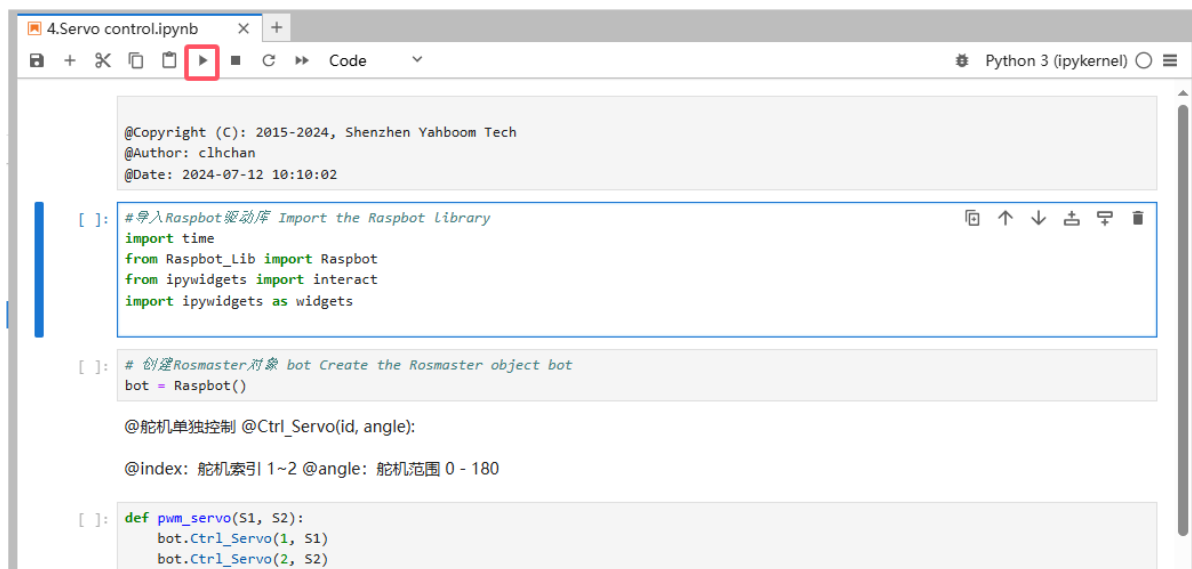
Enter the source code path and double-click the code to be run



Restart the kernel and clear all outputs



Click the first code block, then click the run button to start running one by one



After the program runs, as the code block runs, we can use the slider to control the angle of the servo

