03. Translation of the car

1. Learning objectives

Control the left and right translation of the car.

2. Experimental preparation

As shown in the figure below, the motor needs to be connected to the expansion board.
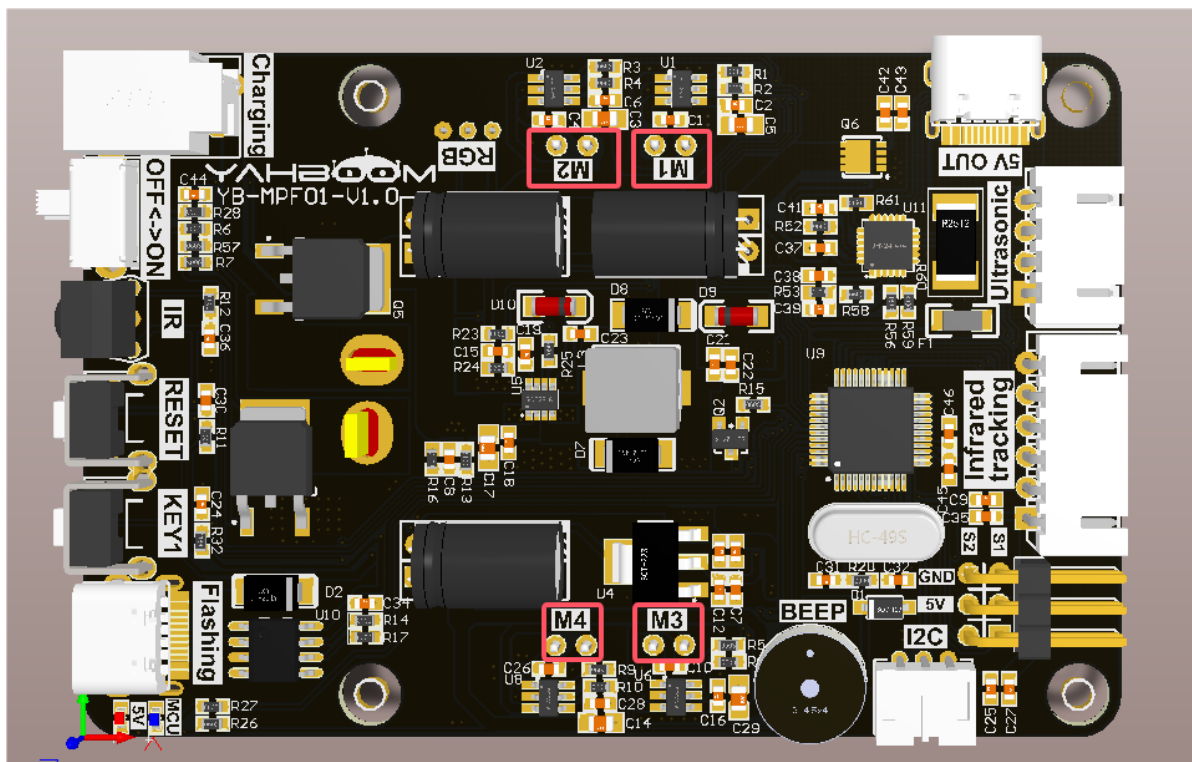
3. Core code analysis

Direction of the car

q w e

a-- | --d

z x c

McLumk_Wheel_Sports library function required to control the movement of the car:

```
move_right(speed)
```

Parameter explanation: Control the right translation of the car

speed: [0,255], the larger the value, the faster the right translation speed

Return value: None.

```
move_left(speed)
```

Parameter explanation: Control the car to move left

speed: [0,255], the larger the value, the faster the left translation
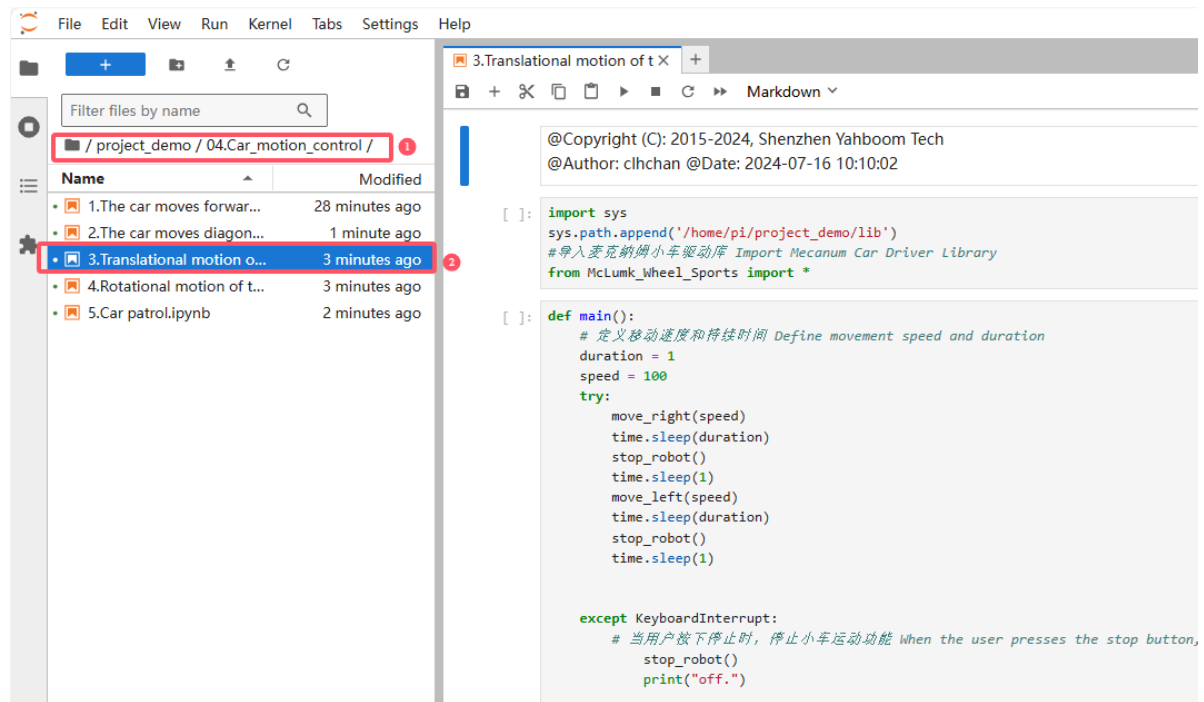
Return value: None.

Source code path: project_demo/04.Car_motion_control
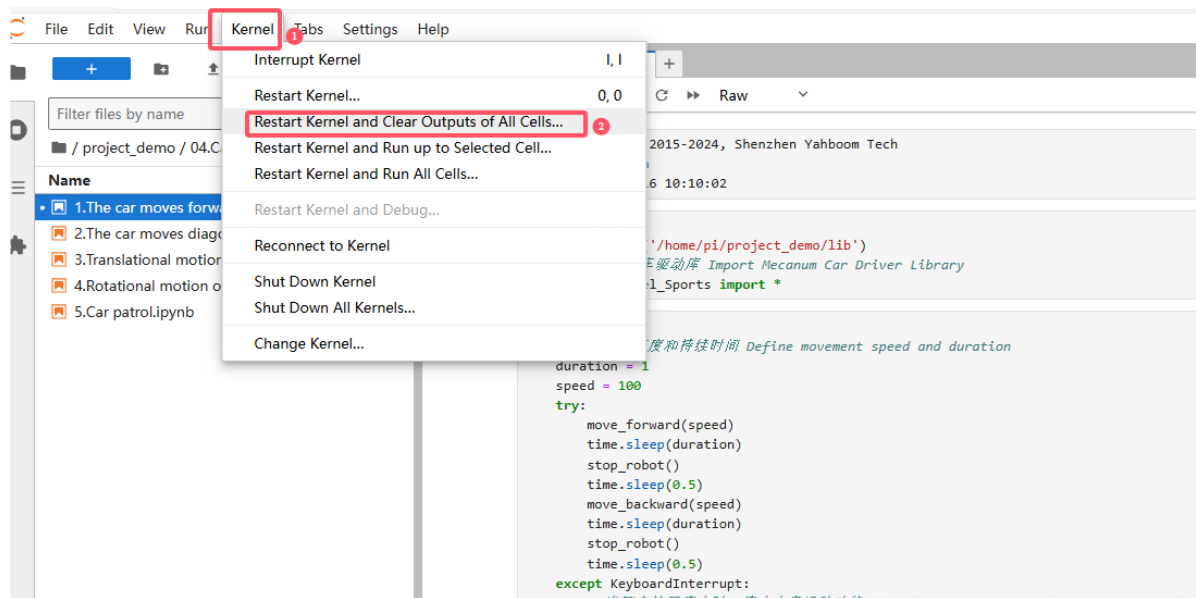
Library path: project_demo/lib

4. Experimental phenomenon

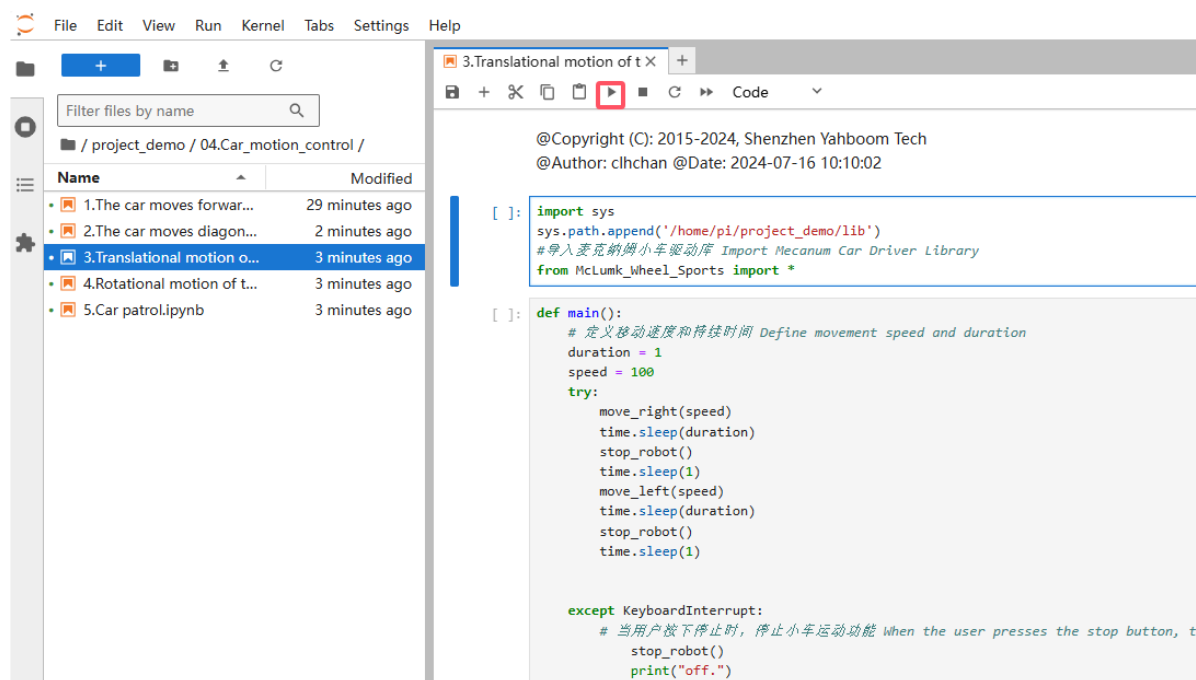Turn on the robot, open the computer browser to enter the Jupyter lab editor

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 blocks run, we can see that the car moves left for 1 second, right for 1 second, and finally stops.