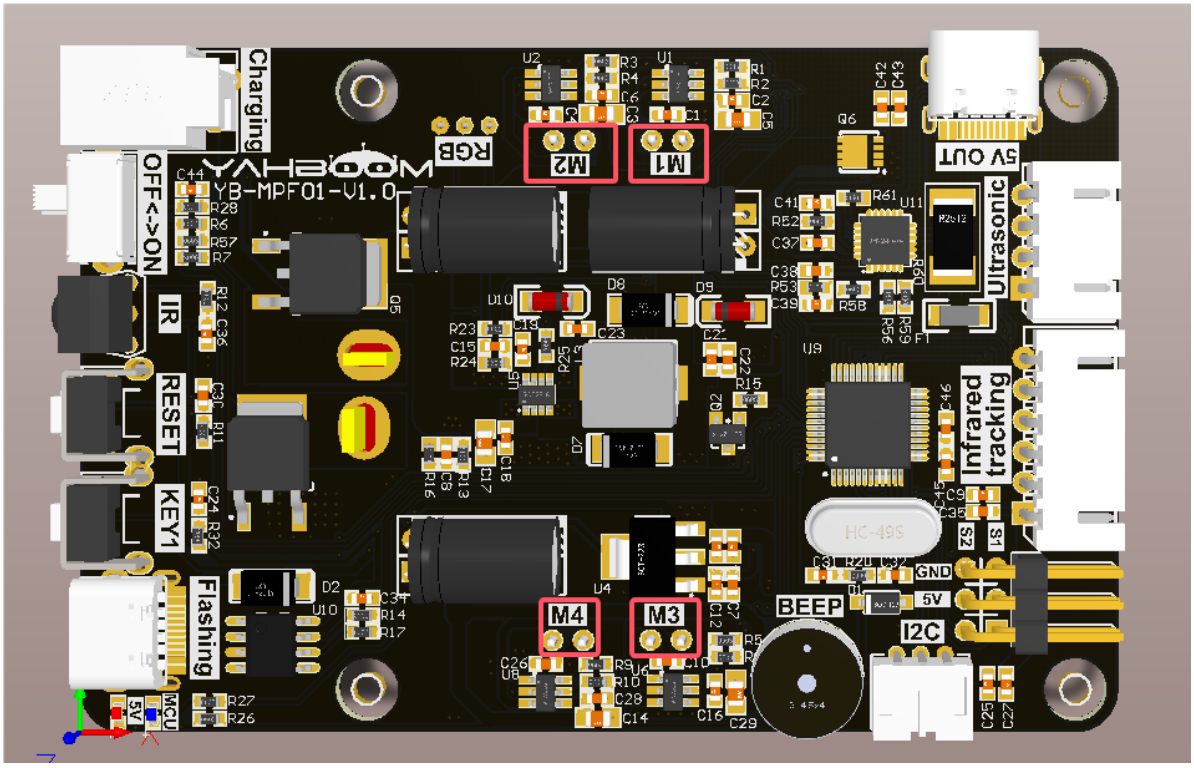
02. Car turning motion

1. Learning objectives

Control the car to turn left and right.

2. Experimental preparation

As shown in the figure below, the motor needs to be connected to the expansion board.



3. Core code analysis

Ordinary_wheel_motion library function required to control the car's motion:

```
turn_right(speed)
```

Parameter explanation: Control the car to turn right

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

Return value: None.

```
turn_left(speed)
```

Parameter explanation: Control the car to turn left

speed: [0,255], the larger the value, the faster the left turn

Return value: None.

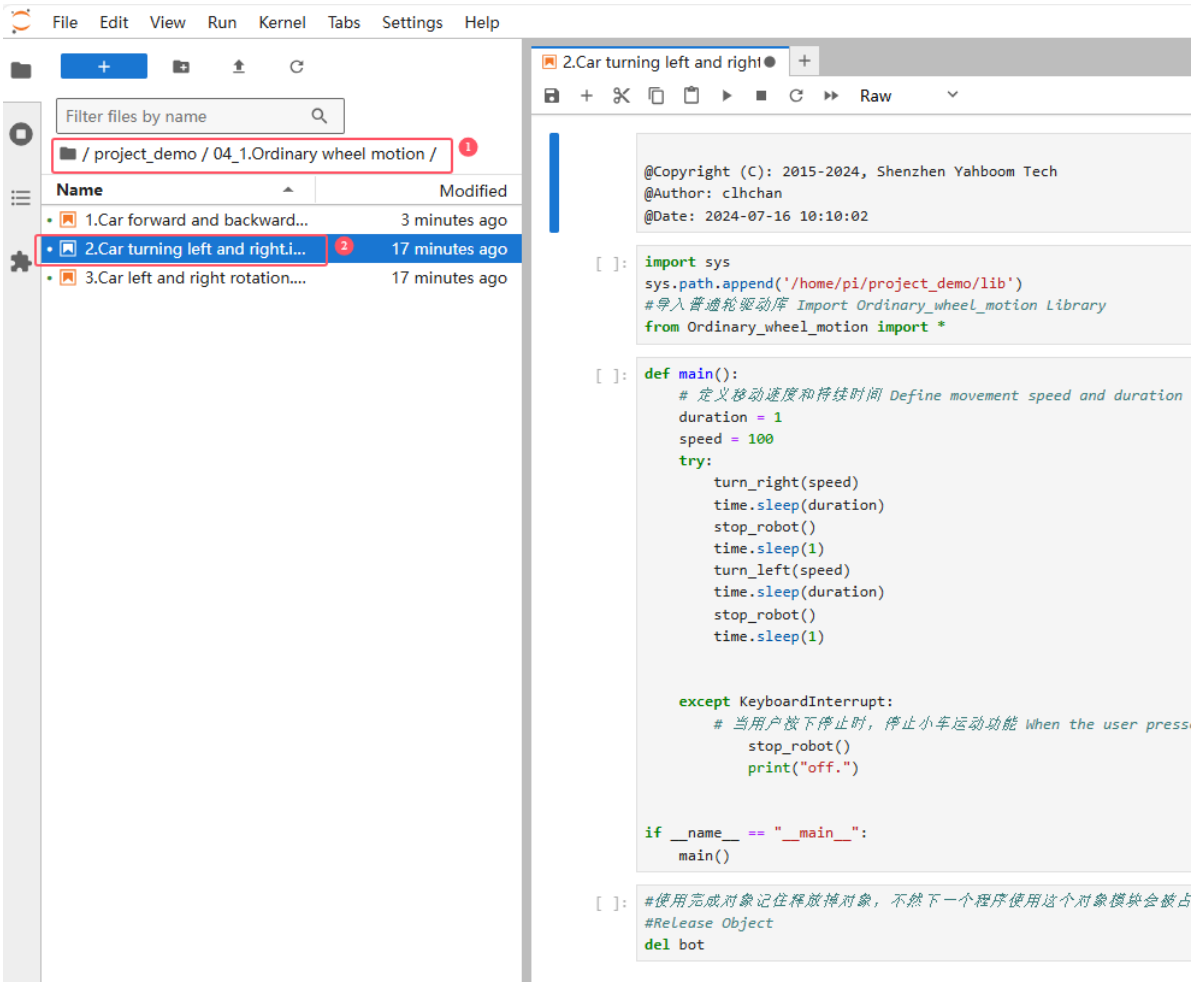
Source code path: project_demo/04_1.Ordinary wheel motion

Library path: project_demo/lib

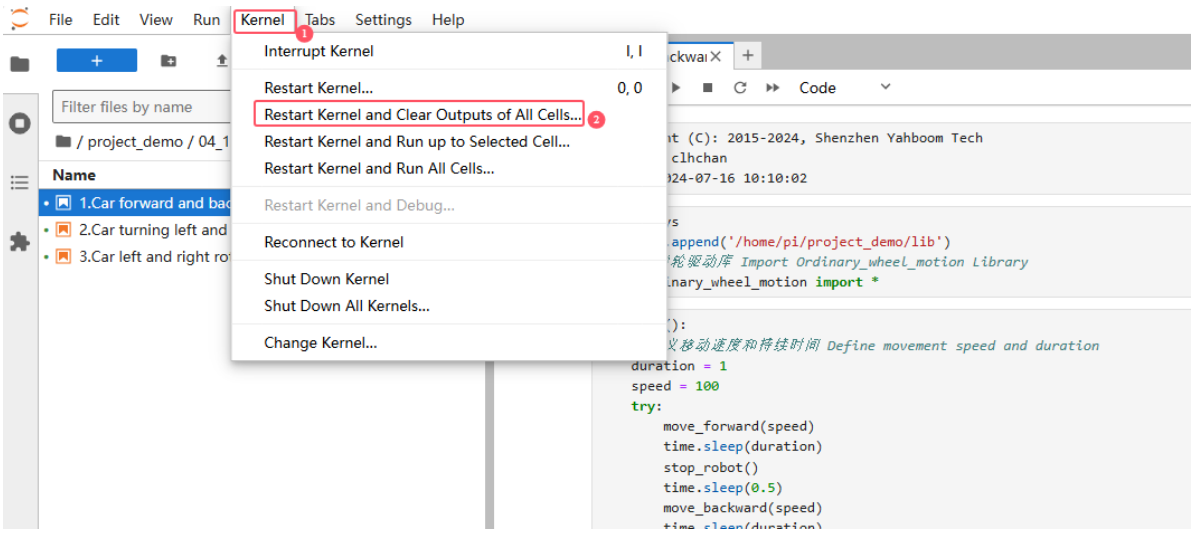
4. Experimental phenomenon

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

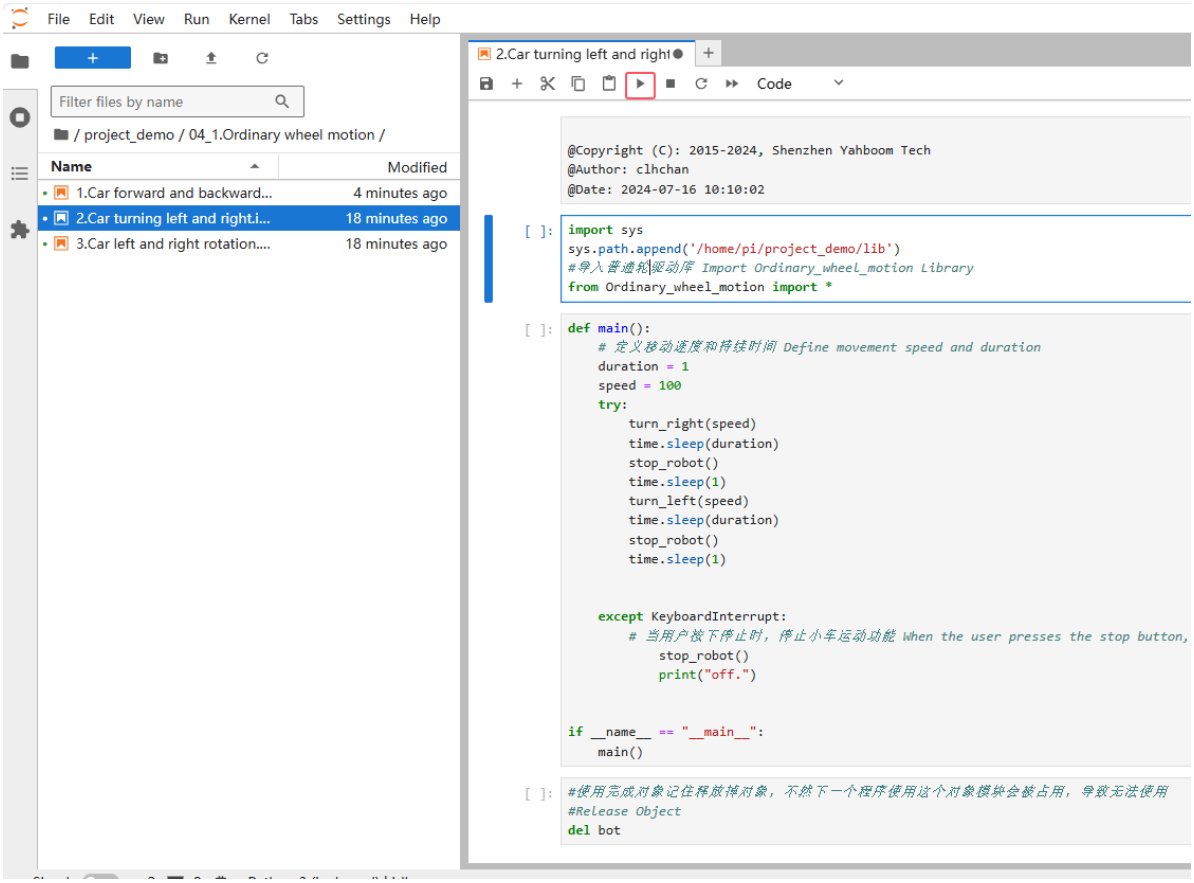
Enter the source code path and double-click the code to be run



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 turns right for 1 second, turns left for 1 second, and finally stops.