

# EV3 LESSONS



## Basic Turning

By Sanjay and Arvind Seshan

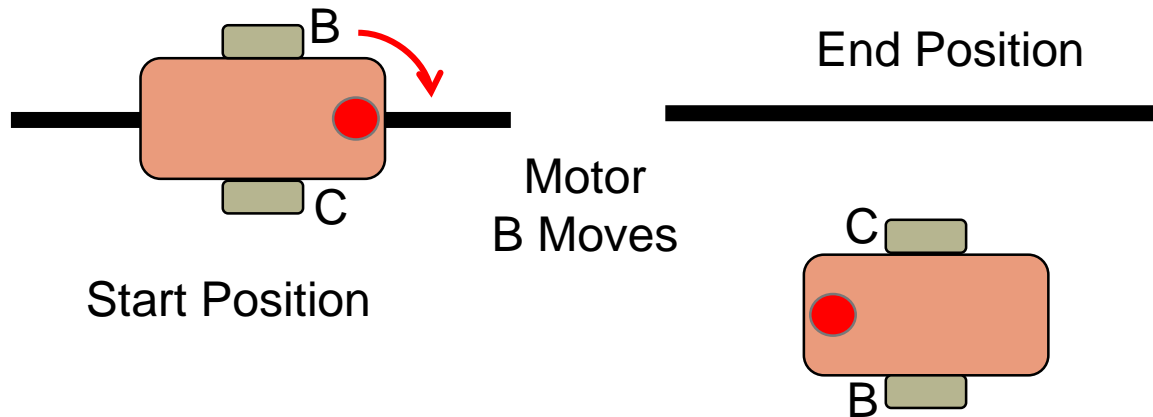
BEGINNER PROGRAMMING LESSON

# LESSON OBJECTIVES

- 1. Learn to turn the robot a desired number of degrees**
- 2. Learn the differences between Spin and Pivot Turns**
- 3. Learn how to program two different type of turns**
- 4. Learn to write pseudocode**

# PIVOT VS. SPIN TURNS

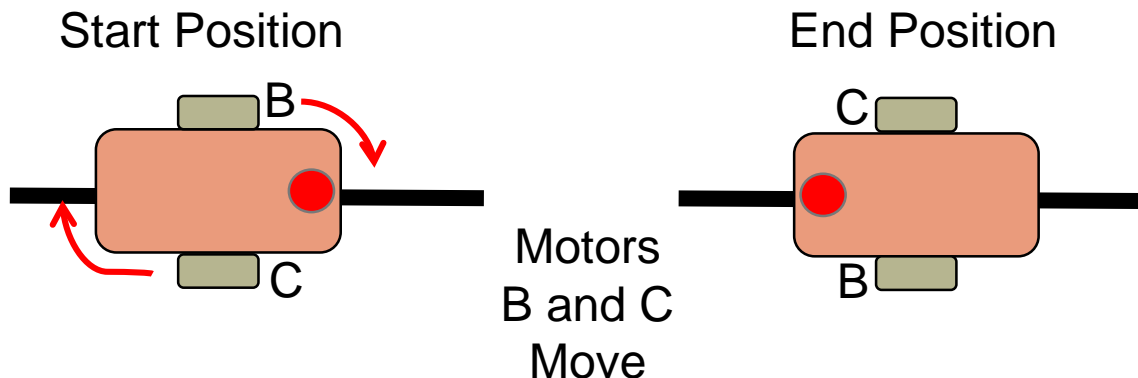
## 180 Degree Pivot Turn



Notice where the robot ends in both pictures after a 180 degree turn.

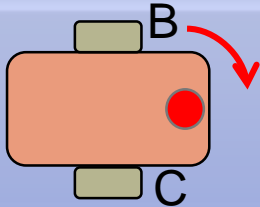
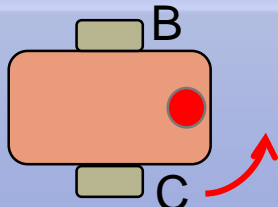
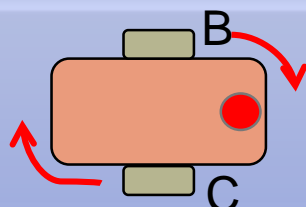
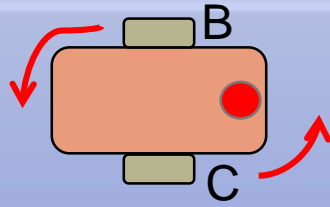
In the Spin Turn, the robot moves a lot less and that makes Spin Turns are great for tight positions. Spin turns tend to be a bit faster but also a little less accurate.

## 180 Degree Spin Turn

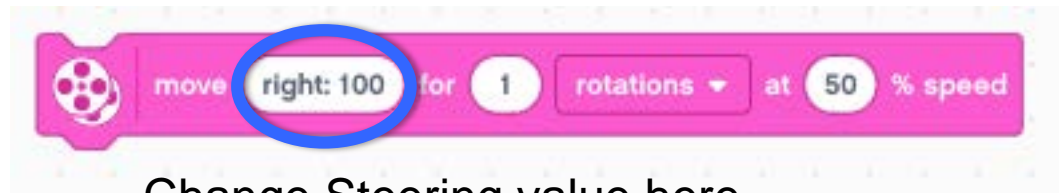


So when you need to make turns, you should decide which turn is best for you!

# HOW TO MAKE PIVOT AND SPIN TURNS


Steering Value			
50	-50	100	-100
			
Pivot Turn Right	Pivot Turn Left	Spin Turn Right	Spin Turn Left

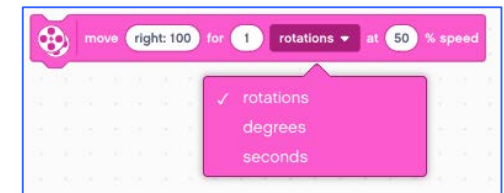
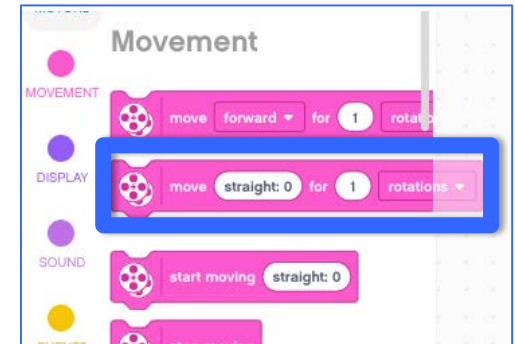
Move Steering  
Block



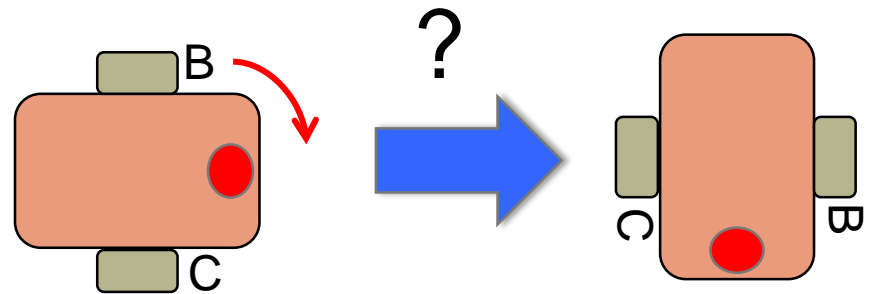
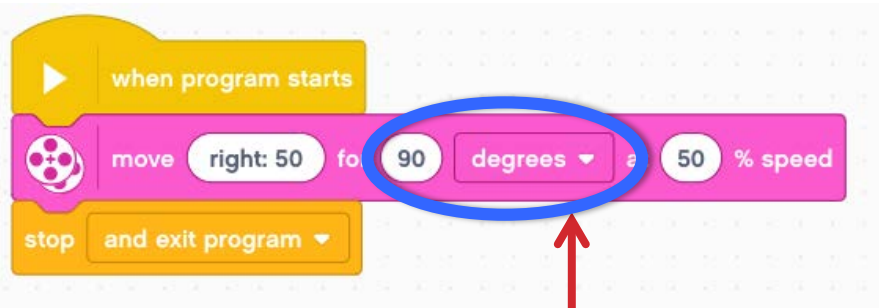
Change Steering value here

# MOVE STEERING

- Found in the movement tab in the palette
- The first input (by default straight) determines the steering value. It ranges -100 to 100.
- The second input determines the distance to travel and its unit (rotations, degrees, or seconds). We will be using degrees.
- The 3<sup>rd</sup> input determines the speed of the robot (range of -100 to 100).
- Tip: use the Control block Stop (  ) to end the program at the end of your project



# MAKING A PIVOT TURN FOR 90 DEGREES

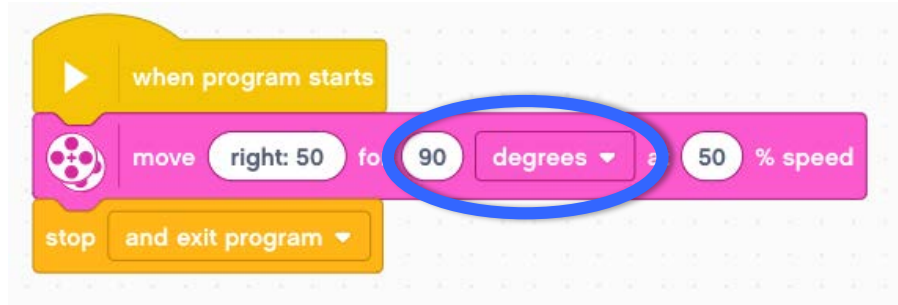


Program your robot to turn 90 degrees  
Does the robot actually turn 90 degrees if you just  
pick 90 degrees for distance?

Ans. NO! Solution on next  
page

# HOW DO YOU MAKE THE ROBOT TURN 90 DEGREES?

**Ans. Try using the port view to measure the turn and then input the correct number of degrees. For the EV3 Educator robot, it is 360 degrees.**



# TEACHER INSTRUCTIONS

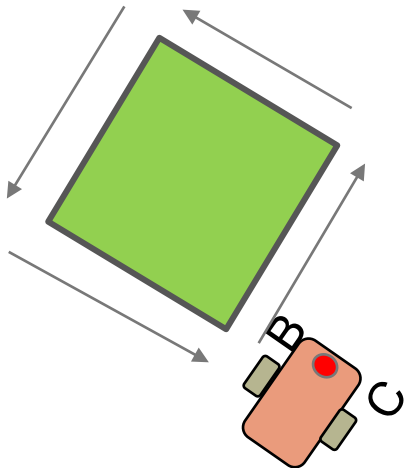
- **Split up class into groups as needed**
- **Give each team a copy of the Turning Challenge Worksheet**
- **Challenge Details are on Slide 9**
- **Discussion Page Slide 10**
- **Challenge Solution on Slide 11**



# TURNING CHALLENGES

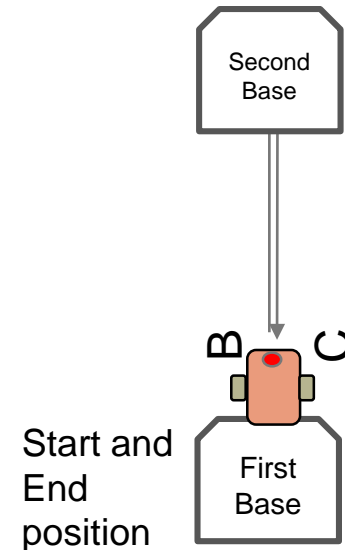
## Challenge 1

- Your robot is a baseball player who has to run to all the bases and go back to home plate.
- Can you program your robot to move forward and then turn left?
- Use a square box or tape



## Challenge 2

- Your robot baseball player must run to second base, **turn around** and come back to first.
- Go straight. Turn 180 degrees and return to the same spot.



# CLASS DISCUSSION GUIDE

**Did you try PIVOT and SPIN turns? What did you discover?**

Pivot turns were fine for Challenge 1, but for Challenge 2, if we used Pivot turns, we were farther away from the base.

**What situations would one work better than the other?**

Spin turns are better for tight turns (places where there is not enough space) and you stay closer to your original position.

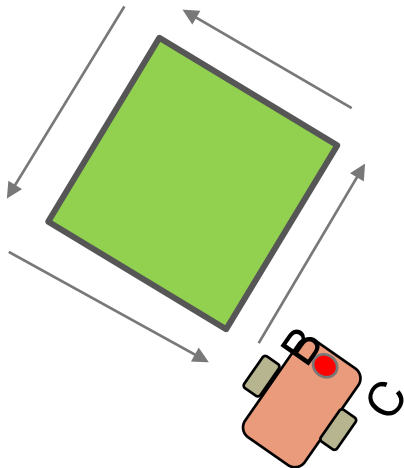
**What is PSEUDOCODE? Why do you think programmers find it useful? (pseudocode is from the worksheet)**

Pseudocode allows programmers to write out their code in plain English before you code in a programming language. It lets you plan and think before you sit down to code. It lets you share your ideas with others you are working with in a common language.

# CHALLENGE SOLUTIONS

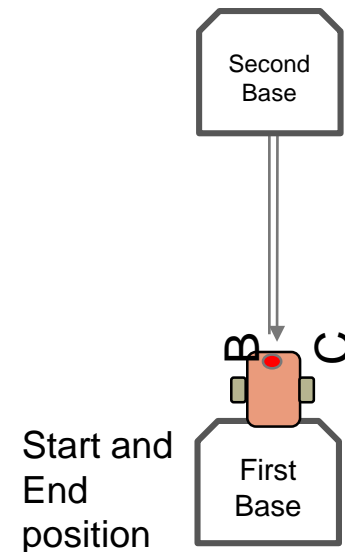
## Challenge 1

You probably used a combination of move steering to go straight and do **pivot turns** to go around the box.



## Challenge 2

You probably used a **spin turn** because it is better for tighter turns and gets you closer to the starting point!



# CREDITS

- This tutorial was created by Sanjay Seshan and Arvind Seshan
- More lessons are available at [www.ev3lessons.com](http://www.ev3lessons.com)



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