**Pi2Go Simulator Programming: WS17 Sample Answers and Trouble Shooting**

**Question 1:** The robot should be initialised (first command), turn left (second command) and then stop (third command).

**Troubleshooting Note:** If the students don’t type cleanup between reimports of the module then there is a good chance they will get error messages talking about socket connections. If this happens it may be necessary to close down both IDLE and the simulator and start again.

**Question 2:**

>>> import turning as my\_turning

>>> my\_turning.pi2go.init()

>>> my\_turning.turn('right')

>>> my\_turning.pi2go.stop()

**Question 3:**

The module should behave just as it did previously – in particular it *won’t* print out the new message in the turn function. This is because the module hasn’t actually been reloaded.

**Question 4:** When **importlib** is used the module correctly reloads and this time the message is printed out when the turn function is executed.

**Exercise:**

import simclient.simrobot as pi2go

import time

def turn(side):

print("message")

if (side == 'left'):

pi2go.spinLeft(10)

else:

pi2go.spinRight(10)

def obstacle(side):

if (side == 'left'):

return pi2go.irLeft()

elif (side == 'right'):

return pi2go.irRight()

else:

return pi2go.irCentre()

pi2go.init()



University of Liverpool, 2019

This work is licensed under a [Creative Commons Attribution-NonCommercial-ShareAlike 4.0 International License](https://creativecommons.org/licenses/by-nc-sa/4.0/).