**Pi2Go Simulator Programming: WS30 & Ex30 Sample Answers**

**NOTE:** Exercises have become sufficiently complex that quite wide variability in answers can be expected.

**WS30**

**Question 1:** When the switch is pressed and there isn’t an obstacle in front of the agent.

**Question 2:** When the switch is pressed and when the agent does not believe ‘started’ because this has not been add to the belief base.

**Question 3:** When the switch is pressed and when the agent believes ‘started’ because this has been add to the belief base.

**Question 4:** When ‘started’ has been added to the belief base.

**Question 5:** When the switch is pressed ‘started’ is added to the belief base (and the agent sleeps for 5 seconds – to allow the switch to be “unpressed”). Once it believes it has started the robot starts to move forward. When the switch is pressed again (or if it is not unpressed within 5 seconds) then the started belief is dropped and a stopping belief is added. Once it believes it is stopped the agent stops the robot, the reasoning cycle and drops the stopping belief.

**Exercise:**

import bdi.pi2goagent as cognitive

import time

agent = cognitive.Pi2GoAgent()

def start\_agent():

agent.add\_belief('started')

time.sleep(5)

return

def stop\_agent():

agent.drop\_belief('started')

agent.add\_belief('stopping')

time.sleep(5)

return

def forward():

agent.robot.forward(10)

return

def turn():

agent.robot.spinLeft(10)

return

def stop\_rule():

agent.robot.stop()

agent.done()

agent.drop\_belief('stopping')

return

start = agent.AND(agent.B('switch\_pressed'), agent.NOT(agent.B('started')))

stop = agent.AND(agent.B('switch\_pressed'), agent.B('started'))

no\_obstacle = agent.AND(agent.B('started'), agent.NOT(agent.B('obstacle\_centre')))

obstacle = agent.AND(agent.B('started'), agent.B('obstacle\_centre'))

agent.add\_condition\_rule(start, start\_agent)

agent.add\_condition\_rule(stop, stop\_agent)

agent.add\_condition\_rule(no\_obstacle, forward)

agent.add\_condition\_rule(obstacle, turn)

agent.add\_condition\_rule(agent.B('stopping'), stop\_rule)

agent.run\_agent()

**Ex30**

**Exercise 1:**

import bdi.pi2goagent as cognitive

import time

agent = cognitive.Pi2GoAgent()

def start\_agent():

agent.add\_belief('started')

time.sleep(5)

return

def stop\_agent():

agent.drop\_belief('started')

agent.add\_belief('stopping')

time.sleep(5)

return

def stop\_rule():

agent.robot.stop()

agent.done()

agent.drop\_belief('stopping')

return

def forward():

agent.robot.forward(10)

return

def left():

agent.robot.spinLeft(10)

return

def right():

agent.robot.spinRight(10)

start = agent.AND(agent.B('switch\_pressed'), agent.NOT(agent.B('started')))

stop = agent.AND(agent.B('switch\_pressed'), agent.B('started'))

on\_line = agent.AND(agent.B('started'), agent.NOT(agent.OR(agent.B('line\_left'), agent.B('line\_right'))))

line\_on\_left = agent.AND(agent.B('started'), agent.B('line\_left'))

line\_on\_right = agent.AND(agent.B('started'), agent.B('line\_right'))

agent.add\_condition\_rule(start, start\_agent)

agent.add\_condition\_rule(stop, stop\_agent)

agent.add\_condition\_rule(on\_line, forward)

agent.add\_condition\_rule(line\_on\_left, left)

agent.add\_condition\_rule(line\_on\_right, right)

agent.add\_condition\_rule(agent.B('stopping'), stop\_rule)

agent.run\_agent()

**Exercise 2:**

import bdi.pi2goagent as cognitive

import time

agent = cognitive.Pi2GoAgent()

def start\_agent():

agent.add\_belief('started')

time.sleep(5)

return

def stop\_agent():

agent.drop\_belief('started')

agent.add\_belief('stopping')

time.sleep(5)

return

def stop\_rule():

agent.robot.stop()

agent.done()

agent.drop\_belief('stopping')

return

def forward():

agent.robot.forward(10)

return

def left():

agent.robot.spinLeft(10)

return

def right():

agent.robot.forward(10)

time.sleep(1)

agent.robot.spinRight(10)

time.sleep(2)

return

start = agent.AND(agent.B('switch\_pressed'), agent.NOT(agent.B('started')))

stop = agent.AND(agent.B('switch\_pressed'), agent.B('started'))

wall\_on\_right = agent.AND(agent.B('started'), agent.AND(agent.B('obstacle\_right'), agent.NOT(agent.B('obstacle\_centre'))))

wall\_in\_front = agent.AND(agent.B('started'), agent.B('obstacle\_centre'))

lost\_wall = agent.AND(agent.B('started'), agent.NOT(agent.OR(agent.B('obstacle\_right'), agent.B('obstacle\_right'))))

floor = agent.AND(agent.B('started'), agent.B('line\_left'))

agent.add\_condition\_rule(start, start\_agent)

agent.add\_condition\_rule(stop, stop\_agent)

agent.add\_condition\_rule(floor, stop\_rule)

agent.add\_condition\_rule(wall\_on\_right, forward)

agent.add\_condition\_rule(wall\_in\_front, left)

agent.add\_condition\_rule(lost\_wall, right)

agent.add\_condition\_rule(agent.B('stopping'), stop\_rule)

agent.run\_agent()



University of Liverpool, 2020

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