**Virtual Pi2Go Programming: The Time Module**



**AIM:** After completing this worksheet you should be able to use commands from Python’s Time module to delay execution of commands on the Pi2Go. You should also be able to explain how to import a module into Python.

**You Need:** To complete this worksheet you need to have a virtual Pi2Go Simulation (see WS1), and to be able to use files to store Programs (see WS5). You also need to know the commands to operate the virtual Pi2Go motors (see WS3).

**If the simulator isn’t already running:**

Start it, and select the Pi2Go robot and default\_world.xml

Now open a new IDLE window.

When we program, we don’t always want to write everything the program should do from scratch. When someone has already solved a problem, for instance delaying the execution of a command, then we would like to be able to use their solution. This is done by importing *modules* (in some languages called libraries) of pre-programmed commands into our program.

You are already using a module in your programs.

The statement import simclient.simrobot as pi2go at the start of all your programs is importing the simulation module which contains the commands for operating your virtual Pi2Go robot, and renaming this module pi2go.

In this worksheet we will use the time module to delay the execution of some of those commands.

Create a file containing the following program and execute it:

import simclient.simrobot as pi2go, time

pi2go.init()

pi2go.forward(10)

time.sleep(10)

pi2go.stop()



**Question 1:** What happens?

**The Sleep Command** The command time.sleep(*seconds*) makes the program pause for the number of seconds before executing the next command.

**Exercise 1:** Adapt the program to make the robot move forward for 20 seconds before stopping.

**Question 2:** What did you change?

**Exercise 2:** Write a program to make the robot wait for 30 seconds, move forward for 10 seconds, turn for 10 seconds and then stop.

Write your program below:

**Remember:** When you have finished working with your robot type:

**pi2go.cleanup()**



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