

130.64.188.124:8000

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# Programming Hub

● Device Connected

Select a page: EV3 Example Code

```
import ev3dev.ev3 as ev3
ev3.Sound.beep()
```

>>>

```
import ev3dev.ev3 as ev3
ev3.Leds.set_color(ev3.Leds.LEFT, ev3.Leds.GREEN)
ev3.Leds.set_color(ev3.Leds.RIGHT, ev3.Leds.GREEN)
```

>>>

```
import ev3dev.ev3 as ev3
ev3.Leds.set_color(ev3.Leds.LEFT, ev3.Leds.YELLOW)
ev3.Leds.set_color(ev3.Leds.RIGHT, ev3.Leds.YELLOW)
```

>>>

```
import ev3dev.ev3 as ev3
ev3.Leds.set_color(ev3.Leds.LEFT, ev3.Leds.RED)
ev3.Leds.set_color(ev3.Leds.RIGHT, ev3.Leds.RED)
```

>>>

```
import ev3dev.ev3 as ev3
motor_left = ev3.LargeMotor('outB')
motor_right = ev3.LargeMotor('outC')
speed = 80 # Set Speed
motor_left.run_direct(duty_cycle_sp=speed)
motor_right.run_direct(duty_cycle_sp=speed)
```

>>>

Debian stretch on LEGO MINDSTORMS EV3!  
Last login: Fri Jun 14 15:40:42 2019 from 130.64.188.124

robot@ev3dev:~\$ python3  
Python 3.5.3 (default, Sep 27 2018, 17:25:39)  
[GCC 6.3.0 20170516] on linux  
Type "help", "copyright", "credits" or "license" for more information.  
>>> import ev3dev.ev3 as ev3  
>>> ev3.Sound.beep()  
<subprocess.Popen object at 0xb6954b90>  
>>>

Enter Command

Clear Terminal Refresh Terminal

Programming Hub

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# Programming Hub

● Device Connected

Select a page: AR Demo

↑

← □ →

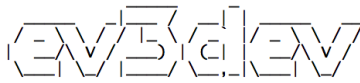
↓

Speed:0/100

Green

Yellow

Red



Debian stretch on LEGO MINDSTORMS EV3!  
Last login: Wed Jul 10 14:34:50 2019 from 10.245.166.90  
robot@ev3dev:~\$

Enter Command Send Command

Clear Terminal Refresh Terminal Begin Python Session Disconnect & Return to Landing

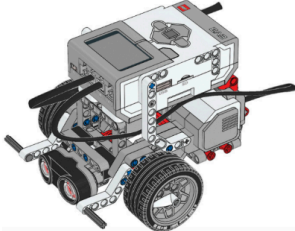
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# Programming Hub

● Device Connected

Select a page: Build A Robot

## 1. Build the Robot with an Ultrasonic Sensor For Collision Detection



[Ultrasonic Driving Base Building Instructions](#)

## 2. Run the Code in a Python Session

### 2.1 Import packages & define inputs/outputs

```
import ev3dev.ev3 as ev3
from time import sleep

us = ev3.UltrasonicSensor() # Connect ultrasonic sensor to any sensor port
us.mode='US-DIST-CM' # Put the US sensor into distance mode.
units = us.units # reports 'cm' even though the sensor measures 'mm'

# Define motor outputs
motor_left = ev3.LargeMotor('outB')
motor_right = ev3.LargeMotor('outC')
```

```
... try: print('Direction: %s' % (direc))
... except NameError: print('invalid character')
>>> def setLED(dist): # set the EV3 LED color based on proximity to
obstruction
... if dist > 50:
...     green()
... elif dist <= 50 and dist >= 10:
...     yellow()
... elif dist < 10:
...     red()
... print('Distance to Obstruction: %s' % (dist))
>>> char = ""
>>> while True:
...     try:
...         char = input() # wait for keyboard input
...         if char != 'q':
...             driveEV3(char)
...             dist = getDist()
...             setLED(dist)
...         else:
...             stop()
...             print('Quitting')
...             raise Exception('quit')
...     except Exception:
...         break
... w
Direction: Forward
Distance to Obstruction: 75.0
s
Direction: Backward
Distance to Obstruction: 43.6
a
Direction: Left
Distance to Obstruction: 42.9
d
Direction: Right
Distance to Obstruction: 57.2
```

Enter Command
Send Command

Clear Terminal
Refresh Terminal
Begin Python Session
Disconnect & Return to Landing