#1 Creating my own function

def my\_function():

    print ("Hello")

    print ("Goodbye")

my\_function()

#2 making the robot jump

def turn\_right():

    turn\_left()

    turn\_left()

    turn\_left()

def jump():

    move()

    turn\_left()

    move()

    turn\_right()

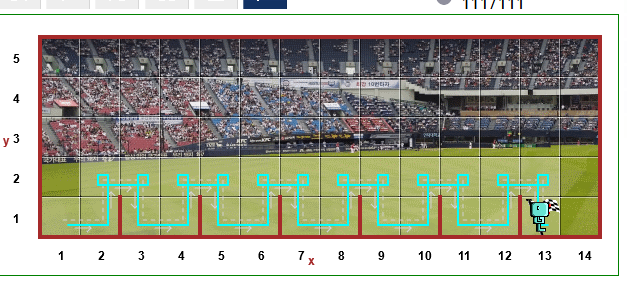
    move()

    turn\_right()

    move()

    turn\_left()

for step in range (6):

    jump()

#3 WHILE loop

def turn\_right():

    turn\_left()

    turn\_left()

    turn\_left()

def jump():

    move()

    turn\_left()

    move()

    turn\_right()

    move()

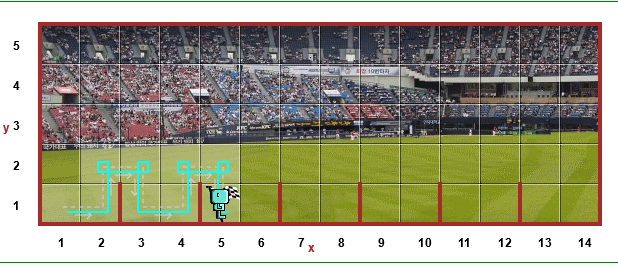
    turn\_right()

    move()

    turn\_left()

while not at\_goal():

    jump()



#4 Making the rotor jump when necessary

 def turn\_right():

    turn\_left()

    turn\_left()

    turn\_left()

def jump():

    turn\_left()

    move()

    turn\_right()

    move()

    turn\_right()

    move()

    turn\_left()

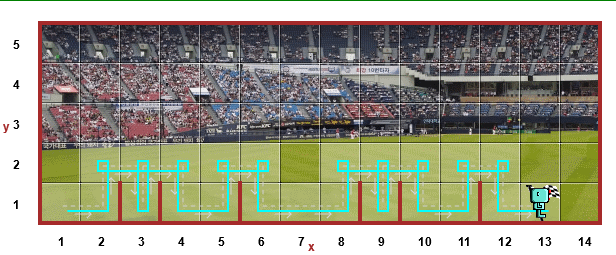
while not at\_goal():

    if front\_is\_clear():

        move()

    elif wall\_in\_front():

        jump()

1

#5 Making the robot run random to the goal

def turn\_right():

    turn\_left()

    turn\_left()

    turn\_left()

def go\_up():

    while wall\_on\_right():

        move()

    turn\_right()

    move()

    turn\_right()

def jump():

    turn\_left()

    go\_up()

while not at\_goal():

    if front\_is\_clear() and not right\_is\_clear():

        move()

    elif wall\_in\_front() and wall\_on\_right():

        turn\_left()

    elif not wall\_on\_right():

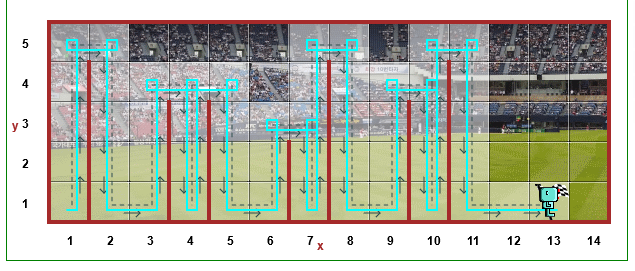
        turn\_right()

        move()

        turn\_right()

        if front\_is\_clear():

            move()



#5 Solucion teacher

def turn\_right():

    turn\_left()

    turn\_left()

    turn\_left()

def jump():

    turn\_left()

    while wall\_on\_right():

        move()

    turn\_right()

    move()

    turn\_right()

    while front\_is\_clear():

        move()

    turn\_left()

while not at\_goal():

    if front\_is\_clear():

        move()

    elif wall\_in\_front():

        jump()

#6 TEST! taking the robot out of the maze

def turn\_right():

    turn\_left()

    turn\_left()

    turn\_left()

while front\_is\_clear():

    move()

turn\_left()

while not at\_goal():

    if wall\_in\_front():

        turn\_left()

    if front\_is\_clear():

        move()

        if right\_is\_clear():

            turn\_right()

