**Virtual Pi2Go Programming: Worksheet and Exercises 11: Sample Answers and Troubleshooting**

**WS11**

**Sample Answer 1:**

Sensor: irCentre(), Motor: forward(10) and spinLeft(10) or spinRight(10)(speed values may vary)

**The Program:**

import simclient.simrobot as pi2go, time

pi2go.init()

time.sleep(30)

while True:

 while not (pi2go.irCentre()):

 pi2go.forward(10)

 while (pi2go.irCentre()):

 pi2go.spinLeft(30)

**Program Modified to Stop Cleanly**

import simclient.simrobot as pi2go, time

pi2go.init()

while not (pi2go.getSwitch()):

 continue

while (pi2go.getSwitch()):

 continue

while not (pi2go.getSwitch()):

 while not (pi2go.irCentre()):

 pi2go.forward(10)

 while (pi2go.irCentre()):

 pi2go.spinLeft(30)

pi2go.stop()

**Ex11**

import simclient.simrobot as pi2go, time

pi2go.init()

while not (pi2go.getSwitch()):

 continue

while (pi2go.getSwitch()):

 continue

while not (pi2go.getSwitch()):

 while (pi2go.irLeftLine()):

 pi2go.spinLeft(10)

 while (not pi2go.irLeftLine() and not pi2go.irRightLine()):

 pi2go.forward(30)

 while (pi2go.irRightLine()):

 pi2go.spinRight(30)

pi2go.stop()



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