**Virtual Pi2Go Programming: WS17 Sample Answers and Trouble Shooting**

**Question 1:** The robot should be initialised (first command), turn left (second command) and then stop (third command).

**Troubleshooting Note:** If the students don’t type cleanup between reimports of the module then there is a good chance they will get error messages talking about socket connections. If this happens it may be necessary to close down both IDLE and the simulator and start again.

**Question 2:**

>>> import turning as my\_turning

>>> my\_turning.pi2go.init()

>>> my\_turning.turn('right')

>>> my\_turning.pi2go.stop()

**Question 3:**

The module should behave just as it did previously – in particular it *won’t* print out the new message in the turn function. This is because the module hasn’t actually been reloaded.

**Question 4:** When **importlib** is used the module correctly reloads and this time the message is printed out when the turn function is executed.

**Exercise:**

import simclient.simrobot as pi2go

import time

def turn(side):

 print("message")

 if (side == 'left'):

 pi2go.spinLeft(10)

 else:

 pi2go.spinRight(10)

def obstacle(side):

 if (side == 'left'):

 return pi2go.irLeft()

 elif (side == 'right'):

 return pi2go.irRight()

 else:

 return pi2go.irCentre()

pi2go.init()



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