**Virtual Pi2Go Programming: WS27 and Ex27 Sample Answers**

**WS27**

**Question 1:** It prints an empty list.

**Question 2:** It created an empy list/array called readings.

**Question 3:** It prints an empty list (same as when data1.print\_readings() was called).

**Question 4:** take\_readings()

**Question 5:** print\_readings()

**Question 6:** The answer will depend upon where boxes have been placed and how many readings have been taken, but it will be a list of floats.

**Question 7:** data2 = DataLogger()

**Question 8:** Each data logger only stores a reading when its own take\_readings() method is called. Therefore the two data loggers have different lists of readings because the objects were moved between taking readings with different loggers.

**Exercise 1:**

import simclient.simrobot as pi2go

class DataLogger:

 def \_\_init\_\_(self):

 self.right\_readings = []

 self.left\_readings = []

 def take\_irRight\_reading(self):

 self.right\_readings.append(pi2go.irRight())

 def take\_irLeft\_reading(self):

 self.left\_readings.append(pi2go.irLeft())

 def take\_reading(self):

 self.right\_readings.append(pi2go.irRight())

 self.left\_readings.append(pi2go.irLeft())

 def print\_irRight\_log(self):

 print(self.right\_readings)

 def print\_irLeft\_log(self):

 print(self.left\_readings)

 def print\_readings(self):

 print("Right Sensor:" + str(self.right\_readings))

 print("Left Sensor:" + str(self.left\_readings))

**Exercise 2:**

import simclient.simrobot as pi2go

class DataLogger:

 def \_\_init\_\_(self, name):

 self.readings = []

 self.logger\_name = name

 def take\_reading(self):

 self.readings.append(pi2go.getDistance())

 def print\_readings(self):

 print(self.readings)

 def get\_name(self):

 return self.logger\_name

 def set\_name(self, name):

 self.logger\_name = name

**Question 9:** The first logger prints its name as logger1 and the second as logger2. This is because they were given different names when initialised.

**Ex27**

**NOTE:** Exercises are reaching sufficient complexity that it is unreasonable to expect answers to be largely similar – particularly in the way functions, methods, fields and classes may be constructed. Sample answers have to be regarded as examples only, not definitive answers.

**Exercise 1:**

import simclient.simrobot as pi2go

import time

class WallFollower:

 def \_\_init\_\_(self):

 print("Initialising")

 def drive\_to\_wall(self):

 while (not pi2go.irCentre() and not pi2go.irLeft() and not pi2go.irRight()):

 pi2go.forward(10)

 pi2go.stop()

 def spin(self, direction):

 if (direction == 'right'):

 pi2go.spinRight(10)

 else:

 pi2go.spinLeft(10)

 def obstacle\_to(self, direction):

 if (direction == 'right'):

 return pi2go.irRight()

 else:

 return pi2go.irLeft()

 def opposite\_direction(self, direction):

 if (direction == 'right'):

 return 'left'

 else:

 return 'right'

 def follow\_wall(self, direction):

 while (not pi2go.getSwitch() == True):

 if (pi2go.irCentre()):

 while(pi2go.irCentre() or self.obstacle\_to(direction)):

 self.spin(self.opposite\_direction(direction))

 elif (self.obstacle\_to(direction)):

 pi2go.forward(10)

 time.sleep(2)

 elif (not self.obstacle\_to(direction)):

 self.spin(direction)

 time.sleep(1)

 pi2go.stop()

**Exercise 2:**

import simclient.simrobot as pi2go

import time

class WallFollower:

 def \_\_init\_\_(self, side):

 self.direction = side

 def drive\_to\_wall(self):

 while (not pi2go.irCentre() and not pi2go.irLeft() and not pi2go.irRight()):

 pi2go.forward(10)

 pi2go.stop()

 def spin(self, direction):

 if (direction == 'right'):

 pi2go.spinRight(10)

 else:

 pi2go.spinLeft(10)

 def obstacle\_to(self):

 if (self.direction == 'right'):

 return pi2go.irRight()

 else:

 return pi2go.irLeft()

 def opposite\_direction(self):

 if (self.direction == 'right'):

 return 'left'

 else:

 return 'right'

 def follow\_wall(self):

 while (not pi2go.irLeftLine()):

 if (pi2go.irCentre()):

 while(pi2go.irCentre() or self.obstacle\_to()):

 self.spin(self.opposite\_direction())

 elif (self.obstacle\_to()):

 pi2go.forward(10)

 time.sleep(2)

 elif (not self.obstacle\_to()):

 self.spin(self.direction)

 time.sleep(1)

 pi2go.stop()

pi2go.init()

right\_wall = WallFollower('right')

left\_wall = WallFollower('left')

right\_wall.follow\_wall()

pi2go.reverse(10)

time.sleep(5)

pi2go.spinRight(10)

time.sleep(5)

left\_wall.follow\_wall()

**Exercise 3:**

import simclient.simrobot as pi2go

import random, time

class MachineLearner():

 def \_\_init\_\_(self, learning\_rate):

 self.learning\_rate = learning\_rate

 self.epsilon = 1

 self.actions = ['forward', 'backward', 'left', 'right']

 self.dictionary = self.action\_reward(self.actions, 1)

 self.rewards = {(1, 1):1, (1, 0):2, (0, 1):1, (0, 0):0}

 def action\_reward(self, action\_list, default):

 action\_rewards = {}

 for i in range(0, 2):

 for j in range(0, 2):

 for k in (action\_list):

 action\_rewards[((i, j), k)] = default

 return action\_rewards

def get\_max(self, state):

 max\_reward = 0

 action = 'forward'

 for act in self.actions:

 if (self.dictionary[(state, act)] > max\_reward):

 action = act

 max\_reward = self.dictionary[(state, act)]

 return action

 def action\_execute(self, action):

 if (action == "forward"):

 pi2go.forward(10)

 elif (action == "backward"):

 pi2go.reverse(10)

 elif (action == "left"):

 pi2go.spinLeft(10)

 elif (action == "right"):

 pi2go.spinRight(10)

 else:

 pi2go.stop()

 def learn(self):

 while (self.epsilon > 0):

 explore = random.random();

 state = (pi2go.irLeftLine(), pi2go.irRightLine())

 if (explore < self.epsilon):

 print("Exploring")

 action = random.choice(self.actions)

 else:

 action = self.get\_max(state)

 self.action\_execute(action)

 time.sleep(3)

 reward = self.rewards[(pi2go.irLeftLine(), pi2go.irRightLine())]

 if (reward == 2):

 self.epsilon = self.epsilon - 0.05

 print("updating epsilon: " + str(self.epsilon))

 self.dictionary[(state, action)] = self.dictionary[(state, action)] + ( reward - self.dictionary[(state, action)]) \* self.learning\_rate

 def follow\_policy(self):

 while (not pi2go.getSwitch() == True):

 state = (pi2go.irLeftLine(), pi2go.irRightLine())

 action = self.get\_max(state)

 self.action\_execute(action)

 time.sleep(3)

 pi2go.stop();

pi2go.init()

learner = MachineLearner(0.5)

learner.learn()

learner.follow\_policy()



 University of Liverpool, 2020

This work is licensed under a [Creative Commons Attribution-NonCommercial-ShareAlike 4.0 International License](https://creativecommons.org/licenses/by-nc-sa/4.0/).