Movimientos

> Los movimientos de mBot2 se pueden definir por tiempo, distancia, ángulo y potencia, gracias a sus precisos motores de paso

Pequeño baile con tiempo definido

```
import cyberpi, mbot2

cyberpi.display.show_label("mBot2 Movement",16,0,0,0)
cyberpi.display.show_label("A:Start Moving!",16,0,20,1)

while True:

    while not cyberpi.controller.is_press('a'):
        pass

    cyberpi.display.show_label("Forward 60 RMP 1 Sec",12,0,40,2)
    mbot2.forward(60,1)
    cyberpi.display.show_label("Backward 60 RMP 1 Sec",12,0,40,2)
    mbot2.backward(60,1)
    cyberpi.display.show_label("Turn Left 60 RMP 1 Sec",12,0,40,2)
    mbot2.turn_left(60,1)
    cyberpi.display.show_label("Turn Right 60 RMP 1 Sec",12,0,40,2)
    mbot2.turn_right(60,1)
    cyberpi.display.show_label("Finished!",12,0,40,2)
```

https://www.youtube.com/embed/pf_htY6PWUw

Pequeño baile con distancia definida

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En este código le decimos que vaya exactamente 100 cm

```
import cyberpi, mbot2

cyberpi.display.show_label("mBot2 Straight",16,0,0,0)
cyberpi.display.show_label("A:Start Moving!",16,0,20,1)

while True:

    while not cyberpi.controller.is_press('a'):
        pass

    cyberpi.display.show_label("Forward 100 cm",12,0,40,2)
    mbot2.straight(100)
    cyberpi.display.show_label("Backward 100 cm",12,0,40,2)
    mbot2.straight(-100)
    cyberpi.display.show_label("Finished!",12,0,40,2)
```

Pequeño baile con ángulos definidos

En este que gire +90º y luego -90º

```
import cyberpi, mbot2

cyberpi.display.show_label("mBot2 Rotation",16,0,0,0)
cyberpi.display.show_label("A:Rotate Left\nB:Rotate Right",16,0,20,1)

while True:

    if cyberpi.controller.is_press('a'):
        cyberpi.display.show_label("Turn Left 90",12,0,60,2)
        mbot2.turn(-90)
    elif cyberpi.controller.is_press('b'):
        cyberpi.display.show_label("Turn Right 90",12,0,60,2)
        mbot2.turn(90)
```

Pequeño baile con potencia definida

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```
import cyberpi, mbot2
from time import sleep

cyberpi.display.show_label("mBot2 EM Power",16,0,0,0)

while not cyberpi.controller.is_press('a'):
        pass

mbot2.drive_power(100, -100)
sleep(1)
mbot2.drive_power(0, 0)
```

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