Sensor de sonidos

Medición de distancia

```
import cyberpi,mbuild


cyberpi.display.show_label("Range:", 16, 0, 0, index = 0)


while True:
    range = mbuild.ultrasonic2.get(index = 1)
    cyberpi.display.show_label(range, 16, 50, 0, index = 1)
```

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Podemos experimentar que es bastante preciso, más que en mBot1

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Este código haría lo mismo pero alarmando que hay obstáculo o no

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```
import cyberpi,mbuild


cyberpi.display.show_label("Range:", 16, 20, 0, index = 0)


while True:
    range = mbuild.ultrasonic2.get(index = 1)
    cyberpi.display.show_label(range, 16, 70, 0, index = 1)

    if range < 10:
        cyberpi.led.on(255,0,0,id="all")
        cyberpi.display.show_label("Obstacle!", 16, 0, 20, index = 2)
    else:
        cyberpi.led.on(0,255,0,id="all")
        cyberpi.display.show_label("No Obstacle", 16, 0, 20, index = 2)
```

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