Sensores de movimiento

Sensor agitación

```
import cyberpi

cyberpi.display.show_label("Shake Value\nA:Start",16,0,0,0)

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

while True:
    shake_value = cyberpi.get_shakeval()
    cyberpi.display.show_label("Shake Value",16,20,0,0)
    cyberpi.display.show_label("{}%".format(shake_value),24,40,50,1)
```

Extraído de https://github.com/PerfecXX/Python-mBot2/blob/main/README.md licencia [MIT](#)

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

Inclinación y rotación

El siguiente programa enseña los dos ángulos de inclinación en eje X e Y y rotación en eje Z

```
import cyberpi

cyberpi.display.show_label("YAW PITCH ROLL\nA:Start",16,0,0,0)

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

```
while True:
    pitch = cyberpi.get_pitch()
    roll = cyberpi.get_roll()
    yaw = cyberpi.get_yaw()

    cyberpi.display.show_label("Yaw\n\nPitch\n\nRoll\n\n",16,0,0,0)
    cyberpi.display.show_label("{}\n\n{}\n\n{}".format(pitch,roll,yaw),16,50,0,1)
```

Extraído de https://github.com/PerfecXX/Python-mBot2/blob/main/README.md licencia [MIT]

El resultado es muy parecido con la función de gyro

```
import cyberpi

cyberpi.reset_rotation(axis='all')
cyberpi.display.show_label("Gyroscope\nA:Start",16,0,0,0)

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

while True:
    x_gyro = cyberpi.get_gyro('x')
    y_gyro = cyberpi.get_gyro('y')
    z_gyro = cyberpi.get_gyro('z')

    cyberpi.display.show_label("X\n\nY\n\nZ\n\n",16,0,0,0)
    cyberpi.display.show_label("{}\n\n{}\n\n{}".format(x_gyro,y_gyro,z_gyro),16,50,0,1)
```

Extraído de https://github.com/PerfecXX/Python-mBot2/blob/main/README.md licencia [MIT]

Y rotation

```
import cyberpi

cyberpi.reset_rotation(axis='all')
cyberpi.display.show_label("Rotation\nA:Start",16,0,0,0)
```

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

while True:
    x_rotate = cyberpi.get_rotation('x')
    y_rotate = cyberpi.get_rotation('y')
    z_rotate = cyberpi.get_rotation('z')

    cyberpi.display.show_label("X\n\nY\n\nZ\n\n",16,0,0,0)
    cyberpi.display.show_label("{}\n\n{}\n\n{}".format(x_rotate,y_rotate,z_rotate),16,50,0,1)
```

Extraído de https://github.com/PerfecXX/Python-mBot2/blob/main/README.md licencia [MIT](#)

https://www.youtube.com/embed/i3HnE8lIdLo

Revision #2
Created 2026-09-11 12:24:22 CEST by Juanjo Mejías
Updated 2026-09-11 12:24:51 CEST by Juanjo Mejías