

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)
```

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<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)
```

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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)
```

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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\nY\nZ\n",16,0,0,0)
```

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

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

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