

Capítulo 18 para Python

```
from spike import App, Motor, ColorSensor
from spike.control import wait_for_seconds
```

```
app = App()
base_motor = Motor('A')
arm_motor = Motor('F')
color_sensor = ColorSensor('D')
```

```
base_motor.set_default_speed(25)
arm_motor.set_default_speed(25)
```

```
# Esto comprobará el color del paquete.
```

```
def check_color():
    arm_motor.run_to_position(235)
    wait_for_seconds(4)
    if color_sensor.get_color() == 'violet':
        base_motor.run_to_position(0)
        arm_motor.run_to_position(25)
        app.play_sound('Triumph')
        arm_motor.run_to_position(240)
    else:
        app.play_sound('Oops')
        arm_motor.run_to_position(25)
        for x in range(3):
            arm_motor.run_for_degrees(-100, speed=100)
            arm_motor.run_for_degrees(100, speed=100)
```

```
# Esto enciende el robot y hace que agarre un paquete de cada lado.
```

```
base_motor.run_to_position(0)
arm_motor.run_to_position(240)
```

```
base_motor.run_to_position(90)
arm_motor.run_to_position(25)
```

```
check_color()
```

```
base_motor.run_to_position(0)
arm_motor.run_to_position(240)
base_motor.run_to_position(270)
arm_motor.run_to_position(25)
```

```
check_color()
```

```
base_motor.run_to_position(0)
arm_motor.run_to_position(240)
```