

Line Follower Methods

read ()

Description	Read the line follower sensor values.
Return Value	A list containing 6 fractional values between 0 and 1, one for each of the 6 sensors on the bottom of the line follower. The higher the number, the more infrared light that has been reflected off the surface below. The order of the values matches that of the sensors on the line follower, with the first value being the left-most sensor reading.
Example	values = line_follower.read() <i>read the line follower and store the results in a list called "values"</i>

position ()

Description	Request the position of the black line relative to the center of the line follower in the form of a string
Return Value	A string (one of "left", "center", "right", "black", "white"). "left" = the black line is on the left side of the line follower "center" = the black line is in the center of the line follower "right" = black line is on the right side of the line follower "black" = the line follower can only see a black surface "white" = the line follower can only see a white surface
Example	direction = line_follower.position() <i>request the position of the black line and store the result in a variable called "direction".</i>

position_val ()

Description	Request the position of the black line relative to the center of the line follower in the form of a number
Return Value	An integer between 0 and 30 0-4 = the black line is on the left side of the line follower 5 = the black line is in the center of the line follower 6-10 = black line is on the right side of the line follower 20 = the line follower can only see a black surface 30 = the line follower can only see a white surface
Example	direction = line_follower.position_val() <i>request the position of the black line and store the result in a variable called "direction".</i>

set_calibration (color)

Description	Read the line follower sensor values, apply these to your current robot instance as values for the stated color , and store them in a calibration file for later re-use (see get_calibration(color)). See the Calibration section above for more information.
Arguments	color: "black" or "white"
Return Value	none
Example	line_follower.set_calibration ("black") <i>read the line follower and store the results as "black" values in the robot's memory and in a calibration file.</i>

get_calibration (color)

Description	Read the calibration values for the stated color from the calibration file and apply them to your current robot instance as example values for the stated color . See the Calibration section above for more information.
Arguments	color: "black" or "white"
Return Value	none
Example	line_follower.get_calibration ("black") <i>read the "black" calibration file and apply these as example values for "black" in the robot's memory.</i>