

# Control the buzzer

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## 1. API Introduction

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The API corresponding to the RGB light is:

### **Arm\_Buzzer\_On(delay=255)**

Function: Turn on the buzzer.

Parameter explanation:

delay: The input range of delay is 1~50. The larger the value, the longer the buzzer will sound. It will automatically turn off after timeout. The delay time is specified as: 1=100 milliseconds, 2=200 milliseconds, and so on. The maximum delay time is 50=5 seconds. If the delay does not pass in a value or delay=255, it means that the buzzer will sound for a long time and needs to be turned off manually.

Return value: None.

### **Arm\_Buzzer\_Off()**

Function explanation: Turn off the buzzer.

Parameter explanation:

No parameters are passed in.

Return value: None

## 2. Code content

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Code path:

```
~/dofbot_pro/dofbot_ctrl/scripts/02.beep.ipynb
```

```
#!/usr/bin/env python3
#coding=utf-8
import time
from Arm_Lib import Arm_Device
```

```
# Get the object of the robot arm
Arm = Arm_Device()
time.sleep(.1)
```

```
# The buzzer automatically sounds and turns off after 100 milliseconds
b_time = 1
Arm.Arm_Buzzer_On(b_time)
time.sleep(1)
```

```
# The buzzer automatically sounds and turns off after 300 milliseconds
b_time = 3
Arm.Arm_Buzzer_On(b_time)
time.sleep(1)
```

```
# The buzzer keeps ringing
Arm.Arm_Buzzer_On()
time.sleep(1)
```

```
# Turn off the buzzer
Arm.Arm_Buzzer_Off()
time.sleep(1)
```

```
del Arm # Release the Arm object p
```

Open the code file from jupyter lab and click the Run the entire notebook button on the jupyter lab toolbar. You can hear the buzzer on the expansion board ring three times in a row, and the latter sounds are longer than the former sounds.



It will automatically exit after the run is completed.