2.Control buzzer

1. API Introduction

The API corresponding to RGB lights 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 sounds. It will automatically turn off after timeout. The delay time is specified: 1=100 milliseconds, 2=200 milliseconds, and so on, up to the maximum The delay time is 50=5 seconds. If delay does not pass in a value or delay=255, it means that the buzzer beeps 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

Code path:

```
~/dofbot_ws/src/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 robotic arm
Arm = Arm_Device()
time.sleep(.1)
```

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

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

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

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

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

Open the 2.beep.ipynb file from jupyter lab and click the Run entire notebook button on the jupyter lab toolbar.You can hear the buzzer on the expansion board beeping three times in a row, and the sound from the back is longer than the sound from the front.

It will automatically exit after the operation is completed.