

Control Buzzer

1. API Introduction

The API corresponding to the buzzer 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 automatically turns off after timeout. Delay time specification: 1=100 milliseconds, 2=200 milliseconds, and so on, with the maximum delay time being 50=5 seconds. If no value is passed for delay or delay=255, it means the buzzer sounds continuously and needs to be manually turned off.
Return value: None.

Arm_Buzzer_Off()

Function: Turn off the buzzer.

Parameter explanation:

No input parameters.
Return value: None

2. Code Content

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 robotic arm object
Arm = Arm_Device()
time.sleep(.1)
```

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

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

```
# Buzzer sounds continuously
Arm.Arm_Buzzer_On()
time.sleep(1)
```

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

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

Open the code 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 sound three times in succession, with each subsequent sound being longer than the previous one.



It will automatically exit after running completes.