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## Robot Alert - Error Sound

Create a long, low-pitched sound to indicate an **ERROR**.

## Objective:

Write a command using node.play\_buzzer(freq, on\_time, off\_time, repeat) to produce a sound that clearly indicates **Error**.

```
In [ ]: import rclpy
    from omni_robot_controller import OmniWheelControlNode # Import control nod
# Initialize ROS2 node
    rclpy.init()
    node = OmniWheelControlNode()
```

## Step-by-step Instructions

- 1. Decide on a **frequency** based on the tone you want (higher = sharper, lower = deeper)
- 2. Set how long the sound plays ( on\_time ) and how long it's off between beeps ( off time )
- 3. Choose how many times it should repeat (repeat)

**Hint:** Try a low frequency (e.g., 300 Hz) with a longer duration (1s) and repeat once.

```
In []: # Write your buzzer command below:
    # Example:
    # node.play_buzzer(1000, 0.2, 0.1, 2)
    node.play_buzzer(
```