

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 node

        # 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(
```