**MicroPython with ESP32**

ESP32 programmeren in MicroPython

1. [Thonny IDE en de REPL ( read, evaluate, print , loop )](#thonny)
2. [Default Modules in MicroPython](#help_modules)
3. [Default builtin Functions in MicroPython](#help_builtins)
4. [De Machine module](#machine)
5. [Classes in de Machine module](#machine_classes)
6. [Initialiseren van een ESP32 pin voor gebruik als digitale Input of Output](#init_pin)
7. [Digitale Output sturen met on(), off() of value()](#dig_out)
8. [Digitale Input lezen met value()](#dig_in)
9. [Tijdsvertragingen met time.sleep() sleep\_ms() sleep\_us()](#tijdsvertragingen)
10. [Timers ONE SHOT of PERIODIC](#timers)
11. [Externe pin interrupts](#externe_pininterrupts)
12. [PWM](#pwm)
13. [ADC](#adc)
14. [Software SPI](#spi_soft)
15. [Hardware SPI](#spi_hard)
16. [I2C](#I2C)
17. [Real time clock RTC](#RTC)
18. [RMT puls generator](#RMT)
19. [1-Wire module](#onewire)
20. [Dallas DS18B20 module](#ds18b20)
21. [NeoPixel module](#neopixel)
22. [Capacitieve touch sensor](#capacitive_touch)
23. [DHT temperature en vochtigheid module](#dht)
24. [WebREPL](#webrepl)
25. [OLED](#oled)
26. [Algemene info en datasheets van de ESP32](#algemene_info)
27. [Specifieke functionaliteit van de ESP32](#specifieke_info)
28. [Pin overzicht ESP32. alternatieve pinnen](#pinoverzicht)
29. [Schema ESP32 WROOM](#schema)
30. lezen en schrijven eigen data
31. uart esp32
32. [Oefeningen](#oefeningen)

Thonny IDE voor het gebruik van micropython met ESP32

![Afbeelding met schermafbeelding

Automatisch gegenereerde beschrijving](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAYABgAAD/4RD0RXhpZgAATU0AKgAAAAgABAE7AAIAAAAOAAAISodpAAQAAAABAAAIWJydAAEAAAAcAAAQ0OocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAFdpbSBWZXJsaW5kZW4AAAWQAwACAAAAFAAAEKaQBAACAAAAFAAAELqSkQACAAAAAzEwAACSkgACAAAAAzEwAADqHAAHAAAIDAAACJoAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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![Afbeelding met tekst

Automatisch gegenereerde beschrijving](data:image/jpeg;base64,/9j/4AAQSkZJRgABAQEAYABgAAD/4RD0RXhpZgAATU0AKgAAAAgABAE7AAIAAAAOAAAISodpAAQAAAABAAAIWJydAAEAAAAcAAAQ0OocAAcAAAgMAAAAPgAAAAAc6gAAAAgAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAFdpbSBWZXJsaW5kZW4AAAWQAwACAAAAFAAAEKaQBAACAAAAFAAAELqSkQACAAAAAzEwAACSkgACAAAAAzEwAADqHAAHAAAIDAAACJoAAAAAHOoAAAAIAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAAA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Automatisch gegenereerde 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<https://docs.micropython.org/en/latest/library/builtins.html>

<https://www.w3schools.com/python/python_ref_functions.asp>

<http://docs.micropython.org/en/latest/library/machine.html>

**>>> help(machine)**

# [machine](http://docs.micropython.org/en/latest/library/machine.html#module-machine) — functions related to the hardware

**De machine module laat ons toe hardware vd ESP32 te gebruiken zoals pinnen , I2C, SPI , UART.**

**Maar ook sleepmodes, interrupts, PWM ed kunnen aangestuurd worden.**

The machine module contains specific functions related to the hardware on a particular board. Most functions in this module allow to achieve direct and unrestricted access to and control of hardware blocks on a system (like CPU, timers, buses, etc.). Used incorrectly, this can lead to malfunction, lockups, crashes of your board, and in extreme cases, hardware damage.

A note of callbacks used by functions and class methods of [**machine**](http://docs.micropython.org/en/latest/library/machine.html#module-machine) module: all these callbacks should be considered as executing in an interrupt context. This is true for both physical devices with IDs >= 0 and “virtual” devices with negative IDs like -1 (these “virtual” devices are still thin shims on top of real hardware and real hardware interrupts). See [Writing interrupt handlers](http://docs.micropython.org/en/latest/reference/isr_rules.html#isr-rules).

## Reset related functions

**machine.reset()**

Resets the device in a manner similar to pushing the external RESET button.

**machine.soft\_reset()**

Performs a soft reset of the interpreter, deleting all Python objects and resetting the Python heap. It tries to retain the method by which the user is connected to the MicroPython REPL (eg serial, USB, Wifi).

**machine.reset\_cause()**

Get the reset cause. See [constants](http://docs.micropython.org/en/latest/library/machine.html#machine-constants) for the possible return values.

## Interrupt related functions

**machine.disable\_irq()**

Disable interrupt requests. Returns the previous IRQ state which should be considered an opaque value. This return value should be passed to the **[enable\_irq()](http://docs.micropython.org/en/latest/library/machine.html" \l "machine.enable_irq" \o "machine.enable_irq)** function to restore interrupts to their original state, before **[disable\_irq()](http://docs.micropython.org/en/latest/library/machine.html" \l "machine.disable_irq" \o "machine.disable_irq)** was called.

**machine.enable\_irq(state)**

Re-enable interrupt requests. The state parameter should be the value that was returned from the most recent call to the **[disable\_irq()](http://docs.micropython.org/en/latest/library/machine.html" \l "machine.disable_irq" \o "machine.disable_irq)** function.

## Power related functions

**machine.freq()**

Returns CPU frequency in hertz.

**machine.idle()**

Gates the clock to the CPU, useful to reduce power consumption at any time during short or long periods. Peripherals continue working and execution resumes as soon as any interrupt is triggered (on many ports this includes system timer interrupt occurring at regular intervals on the order of millisecond).

**machine.sleep()**

**Note**

This function is deprecated, use **[lightsleep()](http://docs.micropython.org/en/latest/library/machine.html" \l "machine.lightsleep" \o "machine.lightsleep)** instead with no arguments.

**machine.lightsleep([time\_ms])**

**machine.deepsleep([time\_ms])**

Stops execution in an attempt to enter a low power state.

If time\_ms is specified then this will be the maximum time in milliseconds that the sleep will last for. Otherwise the sleep can last indefinitely.

With or without a timout, execution may resume at any time if there are events that require processing. Such events, or wake sources, should be configured before sleeping, like [**Pin**](http://docs.micropython.org/en/latest/library/machine.Pin.html#machine.Pin) change or [**RTC**](http://docs.micropython.org/en/latest/library/machine.RTC.html#machine.RTC) timeout.

The precise behaviour and power-saving capabilities of lightsleep and deepsleep is highly dependent on the underlying hardware, but the general properties are:

* A lightsleep has full RAM and state retention. Upon wake execution is resumed from the point where the sleep was requested, with all subsystems operational.
* A deepsleep may not retain RAM or any other state of the system (for example peripherals or network interfaces). Upon wake execution is resumed from the main script, similar to a hard or power-on reset. The **[reset\_cause()](http://docs.micropython.org/en/latest/library/machine.html" \l "machine.reset_cause" \o "machine.reset_cause)** function will return **[machine.DEEPSLEEP](http://docs.micropython.org/en/latest/library/machine.html" \l "machine.machine.DEEPSLEEP" \o "machine.machine.DEEPSLEEP)** and this can be used to distinguish a deepsleep wake from other resets.

**machine.wake\_reason()**

Get the wake reason. See [constants](http://docs.micropython.org/en/latest/library/machine.html#machine-constants) for the possible return values.

Availability: ESP32, WiPy.

## Miscellaneous functions

**machine.unique\_id()**

Returns a byte string with a unique identifier of a board/SoC. It will vary from a board/SoC instance to another, if underlying hardware allows. Length varies by hardware (so use substring of a full value if you expect a short ID). In some MicroPython ports, ID corresponds to the network MAC address.

**machine.time\_pulse\_us(pin, pulse\_level, timeout\_us=1000000, /)**

Time a pulse on the given pin, and return the duration of the pulse in microseconds. The pulse\_level argument should be 0 to time a low pulse or 1 to time a high pulse.

If the current input value of the pin is different to pulse\_level, the function first (\*) waits until the pin input becomes equal to pulse\_level, then (\*\*) times the duration that the pin is equal to pulse\_level. If the pin is already equal to pulse\_level then timing starts straight away.

The function will return -2 if there was timeout waiting for condition marked (\*) above, and -1 if there was timeout during the main measurement, marked (\*\*) above. The timeout is the same for both cases and given by timeout\_us (which is in microseconds).

**machine.rng()**

Return a 24-bit software generated random number.

Availability: WiPy.

## Constants

**machine.IDLE**

**machine.SLEEP**

**machine.DEEPSLEEP**

IRQ wake values.

**machine.PWRON\_RESET**

**machine.HARD\_RESET**

**machine.WDT\_RESET**

**machine.DEEPSLEEP\_RESET**

**machine.SOFT\_RESET**

Reset causes.

**machine.WLAN\_WAKE**

**machine.PIN\_WAKE**

**machine.RTC\_WAKE**

Wake-up reasons.

## Classes

* [class Pin – control I/O pins](http://docs.micropython.org/en/latest/library/machine.Pin.html)
* [class Signal – control and sense external I/O devices](http://docs.micropython.org/en/latest/library/machine.Signal.html)
* [class ADC – analog to digital conversion](http://docs.micropython.org/en/latest/library/machine.ADC.html)
* [class UART – duplex serial communication bus](http://docs.micropython.org/en/latest/library/machine.UART.html)
* [class SPI – a Serial Peripheral Interface bus protocol (master side)](http://docs.micropython.org/en/latest/library/machine.SPI.html)
* [class I2C – a two-wire serial protocol](http://docs.micropython.org/en/latest/library/machine.I2C.html)
* [class RTC – real time clock](http://docs.micropython.org/en/latest/library/machine.RTC.html)
* [class Timer – control hardware timers](http://docs.micropython.org/en/latest/library/machine.Timer.html)
* [class WDT – watchdog timer](http://docs.micropython.org/en/latest/library/machine.WDT.html)
* [class SD – secure digital memory card (cc3200 port only)](http://docs.micropython.org/en/latest/library/machine.SD.html)
* [class SDCard – secure digital memory card](http://docs.micropython.org/en/latest/library/machine.SDCard.html)

**from** **machine** **import** Pin

Initialiseren van pinnen

p0 = Pin(0, Pin.OUT) *# create output pin on GPIO0*

p2 = Pin(2, Pin.IN) *# create input pin on GPIO2*

p4 = Pin(4, Pin.IN, Pin.PULL\_UP) *# enable internal pull-up resistor*

Schrijven naar pinnen

p0.on() *# set pin to "on" (high) level*

p0.off() *# set pin to "off" (low) level*

p0.value(1) *# set pin to on/high*

Lezen van pinnen

a= p2.value()) *# get value, 0 or 1*

print(p2.value()) *# get value, 0 or 1*

Tijdsvertragingen

**import** **time**

time.sleep(1) *# sleep for 1 second*

time.sleep\_ms(500) *# sleep for 500 milliseconds*

time.sleep\_us(10) *# sleep for 10 microseconds*

start = time.ticks\_ms() *# get millisecond counter*

delta = time.ticks\_diff(time.ticks\_ms(), start) *# compute time difference*

## Timers

Virtual (RTOS-based) timers are supported. Use the [machine.Timer](https://docs.micropython.org/en/latest/library/machine.Timer.html" \l "machine-timer) class with timer ID of -1:

**from** **machine** **import** Timer

tim = Timer(-1)

tim.init(period=5000, mode=Timer.ONE\_SHOT, callback=**lambda** t:print(1))

tim.init(period=2000, mode=Timer.PERIODIC, callback=**lambda** t:print(2))

## External interrupts

All pins except number 16 can be configured to trigger a hard interrupt if their input changes. You can set code (a callback function) to be executed on the trigger.

Let’s first define a callback function, which must take a single argument, being the pin that triggered the function. We will make the function just print the pin:

**>>> def** callback(p):

**...**  print('pin change', p)

Next we will create two pins and configure them as inputs:

**>>> from** **machine** **import** Pin

**>>>** p0 = Pin(0, Pin.IN)

**>>>** p2 = Pin(2, Pin.IN)

An finally we need to tell the pins when to trigger, and the function to call when they detect an event:

**>>>** p0.irq(trigger=Pin.IRQ\_FALLING, handler=callback)

**>>>** p2.irq(trigger=Pin.IRQ\_RISING | Pin.IRQ\_FALLING, handler=callback)

We set pin 0 to trigger only on a falling edge of the input (when it goes from high to low), and set pin 2 to trigger on both a rising and falling edge. After entering this code you can apply high and low voltages to pins 0 and 2 to see the interrupt being executed.

A hard interrupt will trigger as soon as the event occurs and will interrupt any running code, including Python code. As such your callback functions are limited in what they can do (they cannot allocate memory, for example) and should be as short and simple as possible.

## PWM (pulse width modulation)

PWM can be enabled on all output-enabled pins. The base frequency can range from 1Hz to 40MHz but there is a tradeoff; as the base frequency increases the duty resolution decreases. See [LED Control](https://docs.espressif.com/projects/esp-idf/en/latest/api-reference/peripherals/ledc.html) for more details.

Use the machine.PWM class:

**from** **machine** **import** Pin, PWM

pwm0 = PWM(Pin(0)) *# create PWM object from a pin*

pwm0.freq() *# get current frequency*

pwm0.freq(1000) *# set frequency*

pwm0.duty() *# get current duty cycle*

pwm0.duty(200) *# set duty cycle*

pwm0.deinit() *# turn off PWM on the pin*

pwm2 = PWM(Pin(2), freq=20000, duty=512) *# create and configure in one go*

## ADC (analog to digital conversion)

On the ESP32 ADC functionality is available on Pins 32-39. Note that, when using the default configuration, input voltages on the ADC pin must be between 0.0v and 1.0v (anything above 1.0v will just read as 4095). Attenuation must be applied in order to increase this usable voltage range.

Use the [machine.ADC](https://docs.micropython.org/en/latest/library/machine.ADC.html" \l "machine-adc) class:

**from** **machine** **import** ADC

adc = ADC(Pin(32)) *# create ADC object on ADC pin*

adc.read() *# read value, 0-4095 across voltage range 0.0v - 1.0v*

adc.atten(ADC.ATTN\_11DB) *# set 11dB input attenuation (voltage range roughly 0.0v - 3.6v)*

adc.width(ADC.WIDTH\_9BIT) *# set 9 bit return values (returned range 0-511)*

adc.read() *# read value using the newly configured attenuation and width*

ESP32 specific ADC class method reference:

**ADC.atten(attenuation)**

This method allows for the setting of the amount of attenuation on the input of the ADC. This allows for a wider possible input voltage range, at the cost of accuracy (the same number of bits now represents a wider range). The possible attenuation options are:

* **ADC.ATTN\_0DB**: 0dB attenuation, gives a maximum input voltage of 1.00v - this is the default configuration
* **ADC.ATTN\_2\_5DB**: 2.5dB attenuation, gives a maximum input voltage of approximately 1.34v
* **ADC.ATTN\_6DB**: 6dB attenuation, gives a maximum input voltage of approximately 2.00v
* **ADC.ATTN\_11DB**: 11dB attenuation, gives a maximum input voltage of approximately 3.6v

**Warning**

Despite 11dB attenuation allowing for up to a 3.6v range, note that the absolute maximum voltage rating for the input pins is 3.6v, and so going near this boundary may be damaging to the IC!

**ADC.width(width)**

This method allows for the setting of the number of bits to be utilised and returned during ADC reads. Possible width options are:

* **ADC.WIDTH\_9BIT**: 9 bit data
* **ADC.WIDTH\_10BIT**: 10 bit data
* **ADC.WIDTH\_11BIT**: 11 bit data
* **ADC.WIDTH\_12BIT**: 12 bit data - this is the default configuration

## Software SPI bus

There are two SPI drivers. One is implemented in software (bit-banging) and works on all pins, and is accessed via the [machine.SPI](https://docs.micropython.org/en/latest/library/machine.SPI.html" \l "machine-spi) class:

**from** **machine** **import** Pin, SPI

*# construct an SPI bus on the given pins*

*# polarity is the idle state of SCK*

*# phase=0 means sample on the first edge of SCK, phase=1 means the second*

spi = SPI(baudrate=100000, polarity=1, phase=0, sck=Pin(0), mosi=Pin(2), miso=Pin(4))

spi.init(baudrate=200000) *# set the baudrate*

spi.read(10) *# read 10 bytes on MISO*

spi.read(10, 0xff) *# read 10 bytes while outputting 0xff on MOSI*

buf = bytearray(50) *# create a buffer*

spi.readinto(buf) *# read into the given buffer (reads 50 bytes in this case)*

spi.readinto(buf, 0xff) *# read into the given buffer and output 0xff on MOSI*

spi.write(b'12345') *# write 5 bytes on MOSI*

buf = bytearray(4) *# create a buffer*

spi.write\_readinto(b'1234', buf) *# write to MOSI and read from MISO into the buffer*

spi.write\_readinto(buf, buf) *# write buf to MOSI and read MISO back into buf*

## Hardware SPI bus

There are two hardware SPI channels that allow faster transmission rates (up to 80Mhz). These may be used on any IO pins that support the required direction and are otherwise unused (see [Pins and GPIO](https://docs.micropython.org/en/latest/esp32/quickref.html#pins-and-gpio)) but if they are not configured to their default pins then they need to pass through an extra layer of GPIO multiplexing, which can impact their reliability at high speeds. Hardware SPI channels are limited to 40MHz when used on pins other than the default ones listed below.

|  | **HSPI (id=1)** | **VSPI (id=2)** |
| --- | --- | --- |
| sck | 14 | 18 |
| mosi | 13 | 23 |
| miso | 12 | 19 |

Hardware SPI has the same methods as Software SPI above:

**from** **machine** **import** Pin, SPI

hspi = SPI(1, 10000000, sck=Pin(14), mosi=Pin(13), miso=Pin(12))

vspi = SPI(2, baudrate=80000000, polarity=0, phase=0, bits=8, firstbit=0, sck=Pin(18), mosi=Pin(23), miso=Pin(19))

## I2C bus

The I2C driver has both software and hardware implementations, and the two hardware peripherals have identifiers 0 and 1. Any available output-capable pins can be used for SCL and SDA. The driver is accessed via the [machine.I2C](https://docs.micropython.org/en/latest/library/machine.I2C.html#machine-i2c) class:

**from** **machine** **import** Pin, I2C

*# construct a software I2C bus*

i2c = I2C(scl=Pin(5), sda=Pin(4), freq=100000)

*# construct a hardware I2C bus*

i2c = I2C(0)

i2c = I2C(1, scl=Pin(5), sda=Pin(4), freq=400000)

i2c.scan() *# scan for slave devices*

i2c.readfrom(0x3a, 4) *# read 4 bytes from slave device with address 0x3a*

i2c.writeto(0x3a, '12') *# write '12' to slave device with address 0x3a*

buf = bytearray(10) *# create a buffer with 10 bytes*

i2c.writeto(0x3a, buf) *# write the given buffer to the slave*

## Real time clock (RTC)

See [machine.RTC](https://docs.micropython.org/en/latest/library/machine.RTC.html" \l "machine-rtc)

**from** **machine** **import** RTC

rtc = RTC()

rtc.datetime((2017, 8, 23, 1, 12, 48, 0, 0)) *# set a specific date and time*

rtc.datetime() *# get date and time*

## Deep-sleep mode

The following code can be used to sleep, wake and check the reset cause:

**import** **machine**

*# check if the device woke from a deep sleep*

**if** machine.reset\_cause() == machine.DEEPSLEEP\_RESET:

print('woke from a deep sleep')

*# put the device to sleep for 10 seconds*

machine.deepsleep(10000)

Notes:

* Calling deepsleep() without an argument will put the device to sleep indefinitely
* A software reset does not change the reset cause
* There may be some leakage current flowing through enabled internal pullups. To further reduce power consumption it is possible to disable the internal pullups:
* p1 = Pin(4, Pin.IN, Pin.PULL\_HOLD)

After leaving deepsleep it may be necessary to un-hold the pin explicitly (e.g. if it is an output pin) via:

p1 = Pin(4, Pin.OUT, **None**)

## RMT

The RMT (Remote Control) module, specific to the ESP32, was originally designed to send and receive infrared remote control signals. However, due to a flexible design and very accurate (as low as 12.5ns) pulse generation, it can also be used to transmit or receive many other types of digital signals:

**import** **esp32**

**from** **machine** **import** Pin

r = esp32.RMT(0, pin=Pin(18), clock\_div=8)

r *# RMT(channel=0, pin=18, source\_freq=80000000, clock\_div=8)*

*# The channel resolution is 100ns (1/(source\_freq/clock\_div)).*

r.write\_pulses((1, 20, 2, 40), start=0) *# Send 0 for 100ns, 1 for 2000ns, 0 for 200ns, 1 for 4000ns*

The input to the RMT module is an 80MHz clock (in the future it may be able to configure the input clock but, for now, it’s fixed). clock\_div divides the clock input which determines the resolution of the RMT channel. The numbers specificed in write\_pulses are multiplied by the resolution to define the pulses.

clock\_div is an 8-bit divider (0-255) and each pulse can be defined by multiplying the resolution by a 15-bit (0-32,768) number. There are eight channels (0-7) and each can have a different clock divider.

So, in the example above, the 80MHz clock is divided by 8. Thus the resolution is (1/(80Mhz/8)) 100ns. Since the start level is 0 and toggles with each number, the bitstream is 0101 with durations of [100ns, 2000ns, 100ns, 4000ns].

For more details see Espressif’s [ESP-IDF RMT documentation.](https://docs.espressif.com/projects/esp-idf/en/latest/api-reference/peripherals/rmt.html).

## OneWire driver

The OneWire driver is implemented in software and works on all pins:

**from** **machine** **import** Pin

**import** **onewire**

ow = onewire.OneWire(Pin(12)) *# create a OneWire bus on GPIO12*

ow.scan() *# return a list of devices on the bus*

ow.reset() *# reset the bus*

ow.readbyte() *# read a byte*

ow.writebyte(0x12) *# write a byte on the bus*

ow.write('123') *# write bytes on the bus*

ow.select\_rom(b'12345678') *# select a specific device by its ROM code*

There is a specific driver for DS18S20 and DS18B20 devices:

**import** **time**, **ds18x20**

ds = ds18x20.DS18X20(ow)

roms = ds.scan()

ds.convert\_temp()

time.sleep\_ms(750)

**for** rom **in** roms:

print(ds.read\_temp(rom))

Be sure to put a 4.7k pull-up resistor on the data line. Note that the convert\_temp() method must be called each time you want to sample the temperature.

## NeoPixel driver

Use the neopixel module:

**from** **machine** **import** Pin

**from** **neopixel** **import** NeoPixel

pin = Pin(0, Pin.OUT) *# set GPIO0 to output to drive NeoPixels*

np = NeoPixel(pin, 8) *# create NeoPixel driver on GPIO0 for 8 pixels*

np[0] = (255, 255, 255) *# set the first pixel to white*

np.write() *# write data to all pixels*

r, g, b = np[0] *# get first pixel colour*

For low-level driving of a NeoPixel:

**import** **esp**

esp.neopixel\_write(pin, grb\_buf, is800khz)

**Warning**

By default NeoPixel is configured to control the more popular 800kHz units. It is possible to use alternative timing to control other (typically 400kHz) devices by passing timing=0 when constructing the NeoPixel object.

## Capacitive touch

Use the TouchPad class in the machine module:

**from** **machine** **import** TouchPad, Pin

t = TouchPad(Pin(14))

t.read() *# Returns a smaller number when touched*

TouchPad.read returns a value relative to the capacitive variation. Small numbers (typically in the tens) are common when a pin is touched, larger numbers (above one thousand) when no touch is present. However the values are relative and can vary depending on the board and surrounding composition so some calibration may be required.

There are ten capacitive touch-enabled pins that can be used on the ESP32: 0, 2, 4, 12, 13 14, 15, 27, 32, 33. Trying to assign to any other pins will result in a ValueError.

Note that TouchPads can be used to wake an ESP32 from sleep:

**import** **machine**

**from** **machine** **import** TouchPad, Pin

**import** **esp32**

t = TouchPad(Pin(14))

t.config(500) *# configure the threshold at which the pin is considered touched*

esp32.wake\_on\_touch(**True**)

machine.lightsleep() *# put the MCU to sleep until a touchpad is touched*

For more details on touchpads refer to [Espressif Touch Sensor](https://docs.espressif.com/projects/esp-idf/en/latest/api-reference/peripherals/touch_pad.html).

## DHT driver

The DHT driver is implemented in software and works on all pins:

**import** **dht**

**import** **machine**

d = dht.DHT11(machine.Pin(4))

d.measure()

d.temperature() *# eg. 23 (°C)*

d.humidity() *# eg. 41 (% RH)*

d = dht.DHT22(machine.Pin(4))

d.measure()

d.temperature() *# eg. 23.6 (°C)*

d.humidity() *# eg. 41.3 (% RH)*

## WebREPL (web browser interactive prompt)

WebREPL (REPL over WebSockets, accessible via a web browser) is an experimental feature available in ESP32 port. Download web client from <https://github.com/micropython/webrepl> (hosted version available at <http://micropython.org/webrepl>), and configure it by executing:

**import** **webrepl\_setup**

and following on-screen instructions. After reboot, it will be available for connection. If you disabled automatic start-up on boot, you may run configured daemon on demand using:

**import** **webrepl**

webrepl.start()

*# or, start with a specific password*

webrepl.start(password='mypass')

The WebREPL daemon listens on all active interfaces, which can be STA or AP. This allows you to connect to the ESP32 via a router (the STA interface) or directly when connected to its access point.

In addition to terminal/command prompt access, WebREPL also has provision for file transfer (both upload and download). The web client has buttons for the corresponding functions, or you can use the command-line client webrepl\_cli.py from the repository above.

See the MicroPython forum for other community-supported alternatives to transfer files to an ESP32 board.

>> import webrepl\_setup

WebREPL daemon auto-start status: disabled

Would you like to (E)nable or (D)isable it running on boot?

(Empty line to quit)

> E

To enable WebREPL, you must set password for it

New password (4-9 chars): W…..

Confirm password: W…….

Changes will be activated after reboot

Would you like to reboot now? (y/n)

**Nieuwe boot.py ( voeg zelf hetgroene gedeelte toe)**

# This file is executed on every boot (including wake-boot from deepsleep)

#import esp

#esp.osdebug(None)

def do\_connect(ssid, pwd):

import network

sta\_if = network.WLAN(network.STA\_IF)

if not sta\_if.isconnected():

print('connecting to network...')

sta\_if.active(True)

sta\_if.connect(ssid, pwd)

while not sta\_if.isconnected():

pass

print('network config:', sta\_if.ifconfig())

# This file is executed on every boot (including wake-boot from deepsleep)

#import esp

#esp.osdebug(None)

# Attempt to connect to WiFi network

do\_connect('your\_ssid', 'your\_password')

**import webrepl**

**webrepl.start()**

OLED

upload de OLED module naar ESP32 geheugen

<https://github.com/micropython/micropython-esp32/blob/esp32/drivers/display/ssd1306.py>

of

<https://github.com/robert-hh/SH1106>

import de OLED module in main.py

Meestal is de module gebaseerd op de framebuf module, zie :

<http://docs.micropython.org/en/latest/library/framebuf.html>

**classframebuf.FrameBuffer(buffer, width, height, format, stride=width, /)**

Construct a FrameBuffer object. The parameters are:

* buffer is an object with a buffer protocol which must be large enough to contain every pixel defined by the width, height and format of the FrameBuffer.
* width is the width of the FrameBuffer in pixels
* height is the height of the FrameBuffer in pixels
* format specifies the type of pixel used in the FrameBuffer; permissible values are listed under Constants below. These set the number of bits used to encode a color value and the layout of these bits in buffer. Where a color value c is passed to a method, c is a small integer with an encoding that is dependent on the format of the FrameBuffer.
* stride is the number of pixels between each horizontal line of pixels in the FrameBuffer. This defaults to width but may need adjustments when implementing a FrameBuffer within another larger FrameBuffer or screen. The buffer size must accommodate an increased step size.

One must specify valid buffer, width, height, format and optionally stride. Invalid buffer size or dimensions may lead to unexpected errors.

## Drawing primitive shapes

The following methods draw shapes onto the FrameBuffer.

**FrameBuffer.fill(c)**

Fill the entire FrameBuffer with the specified color.

**FrameBuffer.pixel(x, y[, c])**

If c is not given, get the color value of the specified pixel. If c is given, set the specified pixel to the given color.

**FrameBuffer.hline(x, y, w, c)**

**FrameBuffer.vline(x, y, h, c)**

**FrameBuffer.line(x1, y1, x2, y2, c)**

Draw a line from a set of coordinates using the given color and a thickness of 1 pixel. The [**line**](http://docs.micropython.org/en/latest/library/framebuf.html#framebuf.FrameBuffer.line) method draws the line up to a second set of coordinates whereas the **[hline](http://docs.micropython.org/en/latest/library/framebuf.html" \l "framebuf.FrameBuffer.hline" \o "framebuf.FrameBuffer.hline)** and **[vline](http://docs.micropython.org/en/latest/library/framebuf.html" \l "framebuf.FrameBuffer.vline" \o "framebuf.FrameBuffer.vline)** methods draw horizontal and vertical lines respectively up to a given length.

**FrameBuffer.rect(x, y, w, h, c)**

**FrameBuffer.fill\_rect(x, y, w, h, c)**

Draw a rectangle at the given location, size and color. The **[rect](http://docs.micropython.org/en/latest/library/framebuf.html" \l "framebuf.FrameBuffer.rect" \o "framebuf.FrameBuffer.rect)** method draws only a 1 pixel outline whereas the **[fill\_rect](http://docs.micropython.org/en/latest/library/framebuf.html" \l "framebuf.FrameBuffer.fill_rect" \o "framebuf.FrameBuffer.fill_rect)** method draws both the outline and interior.

## Drawing text

**FrameBuffer.text(s, x, y[, c])**

Write text to the FrameBuffer using the the coordinates as the upper-left corner of the text. The color of the text can be defined by the optional argument but is otherwise a default value of 1. All characters have dimensions of 8x8 pixels and there is currently no way to change the font.

## Other methods

**FrameBuffer.scroll(xstep, ystep)**

Shift the contents of the FrameBuffer by the given vector. This may leave a footprint of the previous colors in the FrameBuffer.

**FrameBuffer.blit(fbuf, x, y[, key])**

Draw another FrameBuffer on top of the current one at the given coordinates. If key is specified then it should be a color integer and the corresponding color will be considered transparent: all pixels with that color value will not be drawn.

This method works between FrameBuffer instances utilising different formats, but the resulting colors may be unexpected due to the mismatch in color formats.

## Constants

**framebuf.MONO\_VLSB**

Monochrome (1-bit) color format This defines a mapping where the bits in a byte are vertically mapped with bit 0 being nearest the top of the screen. Consequently each byte occupies 8 vertical pixels. Subsequent bytes appear at successive horizontal locations until the rightmost edge is reached. Further bytes are rendered at locations starting at the leftmost edge, 8 pixels lower.

**framebuf.MONO\_HLSB**

Monochrome (1-bit) color format This defines a mapping where the bits in a byte are horizontally mapped. Each byte occupies 8 horizontal pixels with bit 7 being the leftmost. Subsequent bytes appear at successive horizontal locations until the rightmost edge is reached. Further bytes are rendered on the next row, one pixel lower.

**framebuf.MONO\_HMSB**

Monochrome (1-bit) color format This defines a mapping where the bits in a byte are horizontally mapped. Each byte occupies 8 horizontal pixels with bit 0 being the leftmost. Subsequent bytes appear at successive horizontal locations until the rightmost edge is reached. Further bytes are rendered on the next row, one pixel lower.

**framebuf.RGB565**

Red Green Blue (16-bit, 5+6+5) color format

**framebuf.GS2\_HMSB**

Grayscale (2-bit) color format

**framebuf.GS4\_HMSB**

Grayscale (4-bit) color format

**framebuf.GS8**

Grayscale (8-bit) color format

# General information about the ESP32 port

The ESP32 is a popular WiFi and Bluetooth enabled System-on-Chip (SoC) by Espressif Systems.

## Multitude of boards

There is a multitude of modules and boards from different sources which carry the ESP32 chip. MicroPython tries to provide a generic port which would run on as many boards/modules as possible, but there may be limitations. Espressif development boards are taken as reference for the port (for example, testing is performed on them). For any board you are using please make sure you have a datasheet, schematics and other reference materials so you can look up any board-specific functions.

To make a generic ESP32 port and support as many boards as possible the following design and implementation decision were made:

* GPIO pin numbering is based on ESP32 chip numbering. Please have the manual/pin diagram of your board at hand to find correspondence between your board pins and actual ESP32 pins.
* All pins are supported by MicroPython but not all are usable on any given board. For example pins that are connected to external SPI flash should not be used, and a board may only expose a certain selection of pins.

## Technical specifications and SoC datasheets

The datasheets and other reference material for ESP32 chip are available from the vendor site: <https://www.espressif.com/en/support/download/documents?keys=esp32> . They are the primary reference for the chip technical specifications, capabilities, operating modes, internal functioning, etc.

For your convenience, some of technical specifications are provided below:

* Architecture: Xtensa Dual-Core 32-bit LX6
* CPU frequency: up to 240MHz
* Total RAM available: 528KB (part of it reserved for system)
* BootROM: 448KB
* Internal FlashROM: none
* External FlashROM: code and data, via SPI Flash; usual size 4MB
* GPIO: 34 (GPIOs are multiplexed with other functions, including external FlashROM, UART, etc.)
* UART: 3 RX/TX UART (no hardware handshaking), one TX-only UART
* SPI: 4 SPI interfaces (one used for FlashROM)
* I2C: 2 I2C (bitbang implementation available on any pins)
* I2S: 2
* ADC: 12-bit SAR ADC up to 18 channels
* DAC: 2 8-bit DACs
* RMT: 8 channels allowing accurate pulse transmit/receive
* Programming: using BootROM bootloader from UART - due to external FlashROM and always-available BootROM bootloader, the ESP32 is not brickable

For more information see the ESP32 datasheet: <https://www.espressif.com/sites/default/files/documentation/esp32_datasheet_en.pdf>

MicroPython is implemented on top of the ESP-IDF, Espressif’s development framework for the ESP32. This is a FreeRTOS based system. See the [ESP-IDF Programming Guide](https://docs.espressif.com/projects/esp-idf/en/latest/index.html) for details.

# functionality specific to the ESP32

**esp.flash\_size()**

Read the total size of the flash memory.

**esp.flash\_user\_start()**

Read the memory offset at which the user flash space begins.

**esp32.wake\_on\_touch(wake)**

Configure whether or not a touch will wake the device from sleep. wake should be a boolean value.

**esp32.wake\_on\_ext0(pin, level)**

Configure how EXT0 wakes the device from sleep. pin can be **None** or a valid Pin object. level should be **esp32.WAKEUP\_ALL\_LOW** or **esp32.WAKEUP\_ANY\_HIGH**.

**esp32.wake\_on\_ext1(pins, level)**

Configure how EXT1 wakes the device from sleep. pins can be **None** or a tuple/list of valid Pin objects. level should be **esp32.WAKEUP\_ALL\_LOW** or **esp32.WAKEUP\_ANY\_HIGH**.

**esp32.raw\_temperature()**

Read the raw value of the internal temperature sensor, returning an integer.

**esp32.hall\_sensor()**

Read the raw value of the internal Hall sensor, returning an integer.

**esp32.idf\_heap\_info(capabilities)**

Returns information about the ESP-IDF heap memory regions. One of them contains the MicroPython heap and the others are used by ESP-IDF, e.g., for network buffers and other data. This data is useful to get a sense of how much memory is available to ESP-IDF and the networking stack in particular. It may shed some light on situations where ESP-IDF operations fail due to allocation failures. The information returned is not useful to troubleshoot Python allocation failures, use **[micropython.mem\_info()](https://docs.micropython.org/en/latest/library/micropython.html" \l "micropython.mem_info" \o "micropython.mem_info)** instead.

The capabilities parameter corresponds to ESP-IDF’s **MALLOC\_CAP\_XXX** values but the two most useful ones are predefined as [**esp32.HEAP\_DATA**](https://docs.micropython.org/en/latest/library/esp32.html#esp32.HEAP_DATA) for data heap regions and [**esp32.HEAP\_EXEC**](https://docs.micropython.org/en/latest/library/esp32.html#esp32.HEAP_EXEC) for executable regions as used by the native code emitter.

The return value is a list of 4-tuples, where each 4-tuple corresponds to one heap and contains: the total bytes, the free bytes, the largest free block, and the minimum free seen over time.

Example after booting:

**>>> import** **esp32**; esp32.idf\_heap\_info(esp32.HEAP\_DATA)

[(240, 0, 0, 0), (7288, 0, 0, 0), (16648, 4, 4, 4), (79912, 35712, 35512, 35108),

(15072, 15036, 15036, 15036), (113840, 0, 0, 0)]

## Flash partitions

This class gives access to the partitions in the device’s flash memory and includes methods to enable over-the-air (OTA) updates.

**classesp32.Partition(id)**

Create an object representing a partition. id can be a string which is the label of the partition to retrieve, or one of the constants: **BOOT** or **RUNNING**.

**classmethodPartition.find(type=TYPE\_APP, subtype=0xff, label=None)**

Find a partition specified by type, subtype and label. Returns a (possibly empty) list of Partition objects. Note: **subtype=0xff** matches any subtype and **label=None** matches any label.

**Partition.info()**

Returns a 6-tuple **(type, subtype, addr, size, label, encrypted)**.

**Partition.readblocks(block\_num, buf)**

**Partition.readblocks(block\_num, buf, offset)**

**Partition.writeblocks(block\_num, buf)**

**Partition.writeblocks(block\_num, buf, offset)**

**Partition.ioctl(cmd, arg)**

These methods implement the simple and [extended](https://docs.micropython.org/en/latest/library/uos.html#block-device-interface) block protocol defined by **[uos.AbstractBlockDev](https://docs.micropython.org/en/latest/library/uos.html" \l "uos.AbstractBlockDev" \o "uos.AbstractBlockDev)**.

**Partition.set\_boot()**

Sets the partition as the boot partition.

**Partition.get\_next\_update()**

Gets the next update partition after this one, and returns a new Partition object. Typical usage is **Partition(Partition.RUNNING).get\_next\_update()** which returns the next partition to update given the current running one.

**classmethodPartition.mark\_app\_valid\_cancel\_rollback()**

Signals that the current boot is considered successful. Calling **mark\_app\_valid\_cancel\_rollback** is required on the first boot of a new partition to avoid an automatic rollback at the next boot. This uses the ESP-IDF “app rollback” feature with “CONFIG\_BOOTLOADER\_APP\_ROLLBACK\_ENABLE” and an **OSError(-261)** is raised if called on firmware that doesn’t have the feature enabled. It is OK to call **mark\_app\_valid\_cancel\_rollback** on every boot and it is not necessary when booting firmare that was loaded using esptool.

### Constants

**Partition.BOOT**

**Partition.RUNNING**

Used in the [**Partition**](https://docs.micropython.org/en/latest/library/esp32.html#esp32.Partition) constructor to fetch various partitions: **BOOT** is the partition that will be booted at the next reset and **RUNNING** is the currently running partition.

**Partition.TYPE\_APP**

**Partition.TYPE\_DATA**

Used in **[Partition.find](https://docs.micropython.org/en/latest/library/esp32.html" \l "esp32.Partition.find" \o "esp32.Partition.find)** to specify the partition type: **APP** is for bootable firmware partitions (typically labelled **factory**, **ota\_0**, **ota\_1**), and **DATA** is for other partitions, e.g. **nvs**, **otadata**, **phy\_init**, **vfs**.

**esp32.HEAP\_DATA**

**esp32.HEAP\_EXEC**

Used in **[idf\_heap\_info](https://docs.micropython.org/en/latest/library/esp32.html" \l "esp32.idf_heap_info" \o "esp32.idf_heap_info)**.

**Warning**

The current MicroPython RMT implementation lacks some features, most notably receiving pulses and carrier transmit. RMT should be considered a beta feature and the interface may change in the future.

**classesp32.RMT(channel, \*, pin=None, clock\_div=8)**

This class provides access to one of the eight RMT channels. channel is required and identifies which RMT channel (0-7) will be configured. pin, also required, configures which Pin is bound to the RMT channel. clock\_div is an 8-bit clock divider that divides the source clock (80MHz) to the RMT channel allowing the resolution to be specified.

**RMT.source\_freq()**

Returns the source clock frequency. Currently the source clock is not configurable so this will always return 80MHz.

**RMT.clock\_div()**

Return the clock divider. Note that the channel resolution is **1 / (source\_freq / clock\_div)**.

**RMT.wait\_done(timeout=0)**

Returns True if **[RMT.write\_pulses](https://docs.micropython.org/en/latest/library/esp32.html" \l "esp32.RMT.write_pulses" \o "esp32.RMT.write_pulses)** has completed.

If timeout (defined in ticks of **source\_freq / clock\_div**) is specified the method will wait for timeout or until **[RMT.write\_pulses](https://docs.micropython.org/en/latest/library/esp32.html" \l "esp32.RMT.write_pulses" \o "esp32.RMT.write_pulses)** is complete, returning **False** if the channel continues to transmit.

**Warning**

Avoid using wait\_done() if looping is enabled.

**RMT.loop(enable\_loop)**

Configure looping on the channel, allowing a stream of pulses to be indefinitely repeated. enable\_loop is bool, set to True to enable looping.

**RMT.write\_pulses(pulses, start)**

Begin sending pulses, a list or tuple defining the stream of pulses. The length of each pulse is defined by a number to be multiplied by the channel resolution **(1 / (source\_freq / clock\_div))**. start defines whether the stream starts at 0 or 1.

## Ultra-Low-Power co-processor

**classesp32.ULP**

This class provides access to the Ultra-Low-Power co-processor.

**ULP.set\_wakeup\_period(period\_index, period\_us)**

Set the wake-up period.

**ULP.load\_binary(load\_addr, program\_binary)**

Load a program\_binary into the ULP at the given load\_addr.

**ULP.run(entry\_point)**

Start the ULP running at the given entry\_point.

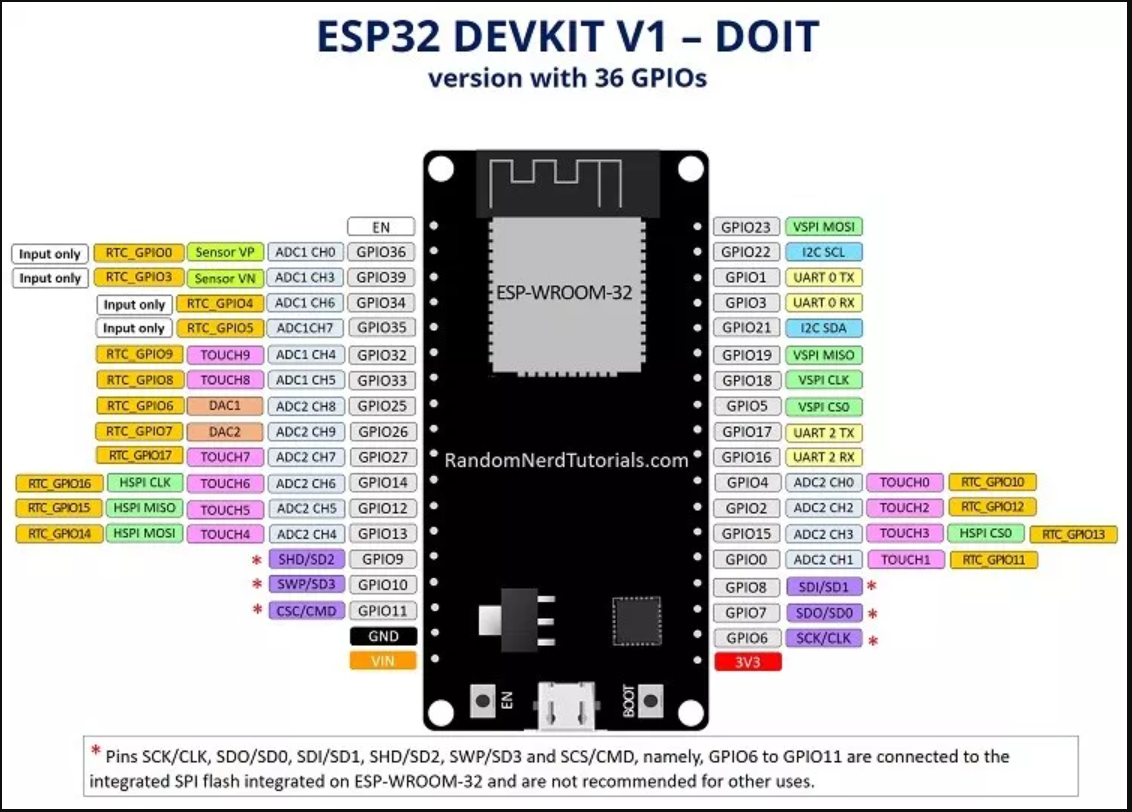
## Constants

**esp32.WAKEUP\_ALL\_LOW**

**esp32.WAKEUP\_ANY\_HIGH**

Selects the wake level for pins.

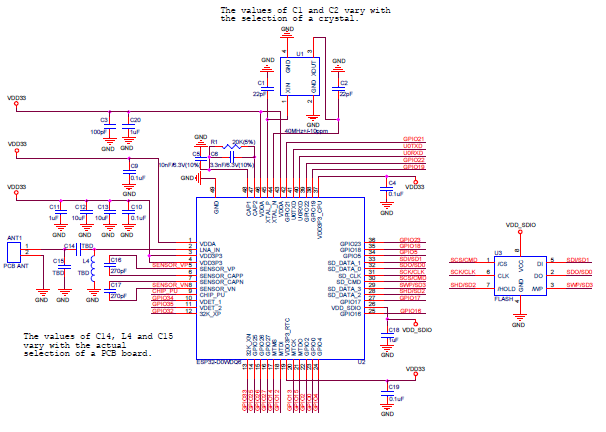
GPIO + Alternative pins of ESP32



**Afbeelding met schermafbeelding

Automatisch gegenereerde beschrijving**

Schema ESP32 WROOM



Lezen en schrijven van eigen data

# The internal filesystem

If your devices has 1Mbyte or more of storage then it will be set up (upon first boot) to contain a filesystem. This filesystem uses the FAT format and is stored in the flash after the MicroPython firmware.

## 3.1. Creating and reading files

MicroPython on the ESP8266 supports the standard way of accessing files in Python, using the built-in open() function.

To create a file try:

>>> f **=** open('data.txt', 'w')

>>> f**.**write('some data')

9

>>> f**.**close()

The “9” is the number of bytes that were written with the write() method. Then you can read back the contents of this new file using:

>>> f **=** open('data.txt')

>>> f**.**read()

'some data'

>>> f**.**close()

Note that the default mode when opening a file is to open it in read-only mode, and as a text file. Specify 'wb' as the second argument to open() to open for writing in binary mode, and 'rb' to open for reading in binary mode.

## 3.2. Listing file and more

The os module can be used for further control over the filesystem. First import the module:

>>> **import** os

Then try listing the contents of the filesystem:

>>> os**.**listdir()

['boot.py', 'port\_config.py', 'data.txt']

You can make directories:

>>> os**.**mkdir('dir')

And remove entries:

>>> os**.**remove('data.txt')

## Start up scripts

There are two files that are treated specially by the ESP8266 when it starts up: boot.py and main.py. The boot.py script is executed first (if it exists) and then once it completes the main.py script is executed. You can create these files yourself and populate them with the code that you want to run when the device starts up.

## Accessing the filesystem via WebREPL

You can access the filesystem over WebREPL using the web client in a browser or via the command-line tool. Please refer to Quick Reference and Tutorial sections for more information about WebREPL.

**UART ESP32**

<https://docs.micropython.org/en/latest/library/machine.UART.html>

ESP32 heeft 3 UART’s UART0,1,2

UART0 wordt gebruikt om te communiceren met PC via USB ( en REPL )

UART1 standaard pinnen zijn niet vrij, kunnen naar andere pinnen omgeleid worden.

UART2 vrij op pinnen 16 en 17

import machine

u2=machine.UART(2, baudrate=9600, rx=16, tx=17, timeout=10)

u2.write("Hello, World!\n")

print(u2.readline())

#\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*\*

from machine import UART

# this uses the UART\_2 default pins TXD=17 and RXD=16

uart2 = UART(2, baudrate=9600)

uart2.init(9600, bits=8, parity=None , stop=1)

#uart2.write('hello')

print("Programma gestart!")

ch= b''

while 1:

if uart2.any()>0:

ch= uart2.readline() # of .read(1)

print(">",ch)

[Oefeningen:](#_top)

1/ Zoek een functie die je clk snelheid ESP32 toont.

2/ Pas de clk snelheid aan naar 20 MHz, check ze en pas terug aan naar de originele clk freq.

3/ Zoek een functie die je unieke ESP32 ID geeft.

4/ Verbind een led met GPIO02 en laat deze knipperen ( 0.2 ON / 0.8 OFF )

5/ Verbind een led met GPIO02 en een drukknop met GPIO 15.

Zorg ervoor dat de LED de drukknop volgt! (tijdens indrukken button LED aan…)

6/ Verbind een led met GPIO02 en een drukknop met GPIO 15.

Drukken op de drukknop toggelt de LED.

7/ Verbind 2 leds met GPIO02 en GPIO4 en een drukknop met GPIO 15.

LEd1 knippert elke seconde ( 0.5/0.5)

Led2 volgt de toestand van de drukknop.

a/ zonder interrupts

b/ met interrupts

8/ Verbind een drukknop met GPIO 15.

Tel hoe vaak deze drukknop wordt ingedrukt en print telkens deze waarde.

9/ Verbind 2 leds met GPIO02 en GPIO4 en een joystick met 3V3/GND en GPIO15.

Bij bewegen naar links gaat led1 harder branden afhankelijk van beweging naar links.

Bij bewegen naar rechts gaat led2 harder branden afhankelijk van beweging naar links.

10/ Verbind een servomotor met GPIO2 en een joystick met 3V3/GND en GPIO15.

Stuur de servomotor met de joystick.

11/ Scan de 1-wire bus nadat je de DS18B20 hebt aangesloten op GPIO26 en 3V3 voeding.

12/ Print de temperatuur van de DS18B20 elke seconde via je REPL.

13/ Toon de temperatuur van 1-wire dallas tempsenoren op je OLED display via een python programma op de ESP32.

Afhankelijk van je display :

<https://github.com/micropython/micropython-esp32/blob/esp32/drivers/display/ssd1306.py>

of

<https://github.com/robert-hh/SH1106>

14/ Toon de via ultrasound gemeten afstand op je OLED scherm.

15/ teken een schuine lijn op je OLED van links boven naar rechts onder.

16/ verplaats een vierkantje 10\*10 op je OLED mbv de joystick.

17/ controleer je 2 leds via een Bluetooth App.

18/ gebruik het protocol led1/on..off led2/on…off om je RP 2 leds verbonden met ESP32 te laten sturen.

Langs de kant vd RP kan je buttons en/of Tkinter GUI gebruiken.

19/ gebruik het protocol but\_1\_4/0..15 om de toestand van de ESP GPIO 12,13,14,15 gelijktijdig naar je RP te versturen.

* Kan je de toestand door RP laten printen?
* Op OLED verbonden met RP tonen?
* In Tkinter GUI tonen?

20/ Meet de Temp met ESP32 en toon deze op een RP GUI en sla deze op in een txt bestand op de RP