

Coche con ESP32-Cam

Proyectos de dos vehiculos utilizando la placa ESP32-Cam:

2º proyecto, utilizamos la ESP32-Cam para controlar en vehiculo, hacer fotos y guardar en Google Drive, utilizando una página Web, los motores los controlamos con una placa Arduino Motor Shield.



Materiales:

- Arduino Motor Shield.
- ESP32-CAM.
- Servomotor.
- Interruptor de encendido
- Bateria de 7,3v.
- Plataforma movil con 2 motores de CC.

Funcionamiento:

Al pulsar en Interruptor de encendido, se activa la ESP32-Cam, creando la pagina web de control (podemos ver la IP en el monitor serie o fijar en el router que le asigne a ese Mac una IP local fija).

Al mismo tiempo podemos ver en la pagina web creada por la ESP32-Cam la imagen en vivo o hacer una foto que se guarda en Google Driver.

Scripts:

ESP32-Cam:

Utiliza archivos:

- ESP32-CamMovil_drive.ino : archivo principal
- Base64.cpp : Para guardar foto en Google Driver

- Base64.h : Para guardar foto en Google Driver
- app_httpd.cpp : Crea página web y controles

ESP32_CamMovil_drive.ino

```

/*
ESP32-CAM
Control remoto de un coche, mediante página web
Guardar foto en Driver
*/

#include "esp_wifi.h"
#include "esp_camera.h"

#include <WiFi.h>
#include "soc/soc.h" //Desactivar problemas de brownout apagado
#include "soc/rstc_cntl_reg.h" //Desactivar problemas de brownout

#define WIFI_SSID "....." //Completar
#define WIFI_PASSWORD "....." //Completar

//---> Define parametros camara
#define CAMERA_MODEL_AI_THINKER
#define PWDN_GPIO_NUM 32
#define RESET_GPIO_NUM -1
#define XCLK_GPIO_NUM 0
#define SIOD_GPIO_NUM 26
#define SIOC_GPIO_NUM 27

#define Y9_GPIO_NUM 35
#define Y8_GPIO_NUM 34
#define Y7_GPIO_NUM 39
#define Y6_GPIO_NUM 36
#define Y5_GPIO_NUM 21
#define Y4_GPIO_NUM 19
#define Y3_GPIO_NUM 18
#define Y2_GPIO_NUM 5
#define VSYNC_GPIO_NUM 25
#define HREF_GPIO_NUM 23
#define PCLK_GPIO_NUM 22
void startCameraServer();

//....> Pines ESP32 a utilizar para el control del coche

#define pinServo 2
#define pinMAOn 12 // velocidad motor 0 - 255
#define pinMADir 13 // Sentido de giro motor
#define pinMBOOn 14
#define pinMBDir 15

//Inicializa motores
void initMotors() {
  //https://randomnerdtutorials.com/esp32-pwm-arduino-ide/
  ledcSetup(3, 2000, 8);
  ledcSetup(4, 2000, 8); // Configura canal para PWM(canal 3,frecuencia 2000hz PWM, 8-bit resolution)
  ledcSetup(5, 2000, 8);
  ledcSetup(6, 2000, 8);
  ledcAttachPin(pinMAOn, 3);
  ledcAttachPin(pinMADir, 4); // Asigna canal PWM a pin GPIO
  ledcAttachPin(pinMBOOn, 5);
  ledcAttachPin(pinMBDir, 6);
}

```

```

//--->Inicilaliza servo
//const int ServoPin = 2;
void initServo() {
    ledcSetup(8, 50, 16); //canal 8 50 hz PWM, 16-bit resolution, range from 3250 to 6500.
    ledcAttachPin(pinServo, 8); // Asigna canal PWM a pin servo
}

void setup() {
    WRITE_PERI_REG(RTC_CNTL_BROWN_OUT_REG, 0); // prevent brownouts by silencing them
    Serial.begin(115200);
    Serial.setDebugOutput(true); //Para activar la salida de debug
    Serial.println();

    camera_config_t config;
    config.ledc_channel = LEDC_CHANNEL_0;
    config.ledc_timer = LEDC_TIMER_0;
    config.pin_d0 = Y2_GPIO_NUM;
    config.pin_d1 = Y3_GPIO_NUM;
    config.pin_d2 = Y4_GPIO_NUM;
    config.pin_d3 = Y5_GPIO_NUM;
    config.pin_d4 = Y6_GPIO_NUM;
    config.pin_d5 = Y7_GPIO_NUM;
    config.pin_d6 = Y8_GPIO_NUM;
    config.pin_d7 = Y9_GPIO_NUM;
    config.pin_xclk = XCLK_GPIO_NUM;
    config.pin_pclk = PCLK_GPIO_NUM;
    config.pin_vsync = VSYNC_GPIO_NUM;
    config.pin_href = HREF_GPIO_NUM;
    config.pin_sscb_sda = SIOD_GPIO_NUM;
    config.pin_sscb_scl = SIOC_GPIO_NUM;
    config.pin_pwdn = PWDN_GPIO_NUM;
    config.pin_reset = RESET_GPIO_NUM;
    config.xclk_freq_hz = 20000000;
    config.pixel_format = PIXFORMAT_JPEG;
    //Inicializa con especificaciones altas para preasignar búferes más grandes
    if(psramFound()){
        config.frame_size = FRAMESIZE_QVGA;
        config.jpeg_quality = 10;
        config.fb_count = 2;
    } else {
        config.frame_size = FRAMESIZE_QVGA;
        config.jpeg_quality = 12;
        config.fb_count = 1;
    }

    // camera init
    esp_err_t err = esp_camera_init(&config);
    if (err != ESP_OK) {
        Serial.printf("Camera init failed with error 0x%x", err);
        return;
    }

    //drop down frame size for higher initial frame rate
    sensor_t * s = esp_camera_sensor_get();
    s->set_framesize(s, FRAMESIZE_QVGA); // VGA|CIF|QVGA|HQVGA|QQVGA ( UXGA? SXGA? XGA? SVGA? )
    s->set_vflip(s, 1);
    s->set_hmirror(s, 1);

    // ---> Control del coche
    initMotors();
    initServo();

    ledcSetup(7, 5000, 8);
    ledcAttachPin(4, 7); //pin4 is LED

    WiFi.mode(WIFI_STA);
    WiFi.begin(WIFI_SSID, WIFI_PASSWORD);

```

```

delay(500);

long int StartTime=millis();
while (WiFi.status() != WL_CONNECTED)
{
    delay(500);
    if ((StartTime+10000) < millis()) break;
}

startCameraServer();

if (WiFi.status() == WL_CONNECTED) {
    Serial.println("");
    Serial.println("WiFi connected");
    Serial.print("Camera Ready! Use 'http://'");
    Serial.print(WiFi.localIP());
    Serial.println(" to connect");
}
else { // Si no se conecta crea Wifi
    Serial.println("");
    Serial.println("WiFi disconnected");
    Serial.print("Camera Ready! Use 'http://'");
    Serial.print(WiFi.softAPIP());
    Serial.println(" to connect");
    char* apssid = "ESP32-CAM";
    char* appassword = "12345678"; //AP password require at least 8 characters.
    WiFi.softAP((WiFi.softAPIP().toString()+"_"+(String)apssid).c_str(), appassword);
}

//---> Muestra un flag inicial
for (int i=0;i<5;i++)
{
    ledcWrite(7,10); // flash led
    delay(50);
    ledcWrite(7,0);
    delay(50);
}
}

void loop() {
    delay(1000);
    // Serial.printf("RSSI: %ld dBm\n",WiFi.RSSI()); //Muestra intensidad señal Wifi
}

```

Base64.cpp

[illegible]

```
"0123456789+/";
```

```
/* 'Private' declarations */
```

```
inline void a3_to_a4(unsigned char * a4, unsigned char * a3);
```

```
inline void a4_to_a3(unsigned char * a3, unsigned char * a4);
```

```
inline unsigned char b64_lookup(char c);
```

```
int base64_encode(char *output, char *input, int inputLen) {
    int i = 0, j = 0;
    int encLen = 0;
    unsigned char a3[3];
    unsigned char a4[4];

    while(inputLen--) {
        a3[i++] = *(input++);
        if(i == 3) {
            a3_to_a4(a4, a3);

            for(i = 0; i < 4; i++) {
                output[encLen++] = pgm_read_byte(&b64_alphabet[a4[i]]);
            }

            i = 0;
        }
    }

    if(i) {
        for(j = i; j < 3; j++) {
            a3[j] = '\0';
        }

        a3_to_a4(a4, a3);

        for(j = 0; j < i + 1; j++) {
            output[encLen++] = pgm_read_byte(&b64_alphabet[a4[j]]);
        }

        while((i++ < 3)) {
            output[encLen++] = '=';
        }
    }
    output[encLen] = '\0';
    return encLen;
}
```

```
int base64_decode(char * output, char * input, int inputLen) {
    int i = 0, j = 0;
    int decLen = 0;
    unsigned char a3[3];
    unsigned char a4[4];

    while (inputLen--) {
        if(*input == '=') {
            break;
        }

        a4[i++] = *(input++);
        if (i == 4) {
            for (i = 0; i < 4; i++) {
                a4[i] = b64_lookup(a4[i]);
            }

            a4_to_a3(a3,a4);

            for (i = 0; i < 3; i++) {
                output[decLen++] = a3[i];
            }
        }
    }
}
```

```

        i = 0;
    }
}

if (i) {
    for (j = i; j < 4; j++) {
        a4[j] = '\0';
    }

    for (j = 0; j < 4; j++) {
        a4[j] = b64_lookup(a4[j]);
    }

    a4_to_a3(a3,a4);

    for (j = 0; j < i - 1; j++) {
        output[decLen++] = a3[j];
    }
}
output[decLen] = '\0';
return decLen;
}

int base64_enc_len(int plainLen) {
    int n = plainLen;
    return (n + 2 - ((n + 2) % 3)) / 3 * 4;
}

int base64_dec_len(char * input, int inputLen) {
    int i = 0;
    int numEq = 0;
    for(i = inputLen - 1; input[i] == '='; i--) {
        numEq++;
    }

    return ((6 * inputLen) / 8) - numEq;
}

inline void a3_to_a4(unsigned char * a4, unsigned char * a3) {
    a4[0] = (a3[0] & 0xfc) >> 2;
    a4[1] = ((a3[0] & 0x03) << 4) + ((a3[1] & 0xf0) >> 4);
    a4[2] = ((a3[1] & 0x0f) << 2) + ((a3[2] & 0xc0) >> 6);
    a4[3] = (a3[2] & 0x3f);
}

inline void a4_to_a3(unsigned char * a3, unsigned char * a4) {
    a3[0] = (a4[0] << 2) + ((a4[1] & 0x30) >> 4);
    a3[1] = ((a4[1] & 0xf) << 4) + ((a4[2] & 0x3c) >> 2);
    a3[2] = ((a4[2] & 0x3) << 6) + a4[3];
}

inline unsigned char b64_lookup(char c) {
    if(c >='A' && c <='Z') return c - 'A';
    if(c >='a' && c <='z') return c - 71;
    if(c >='0' && c <='9') return c + 4;
    if(c == '+') return 62;
    if(c == '/') return 63;
    return -1;
}

```

Base64.h

```
/*
```

```

* Copyright (c) 2013 Adam Rudd.
* See LICENSE for more information
* https://github.com/adamvr/arduino-base64
*/
#ifndef _BASE64_H
#define _BASE64_H

/* b64_alphabet:
*      Description: Base64 alphabet table, a mapping between integers
*                  and base64 digits
*      Notes: This is an extern here but is defined in Base64.c
*/
extern const char b64_alphabet[];

/* base64_encode:
*      Description:
*          Encode a string of characters as base64
*      Parameters:
*          output: the output buffer for the encoding, stores the encoded string
*          input: the input buffer for the encoding, stores the binary to be encoded
*          inputLen: the length of the input buffer, in bytes
*      Return value:
*          Returns the length of the encoded string
*      Requirements:
*          1. output must not be null or empty
*          2. input must not be null
*          3. inputLen must be greater than or equal to 0
*/
int base64_encode(char *output, char *input, int inputLen);

/* base64_decode:
*      Description:
*          Decode a base64 encoded string into bytes
*      Parameters:
*          output: the output buffer for the decoding,
*                  stores the decoded binary
*          input: the input buffer for the decoding,
*                  stores the base64 string to be decoded
*          inputLen: the length of the input buffer, in bytes
*      Return value:
*          Returns the length of the decoded string
*      Requirements:
*          1. output must not be null or empty
*          2. input must not be null
*          3. inputLen must be greater than or equal to 0
*/
int base64_decode(char *output, char *input, int inputLen);

/* base64_enc_len:
*      Description:
*          Returns the length of a base64 encoded string whose decoded
*          form is inputLen bytes long
*      Parameters:
*          inputLen: the length of the decoded string
*      Return value:
*          The length of a base64 encoded string whose decoded form
*          is inputLen bytes long
*      Requirements:
*          None
*/
int base64_enc_len(int inputLen);

/* base64_dec_len:
*      Description:
*          Returns the length of the decoded form of a
*          base64 encoded string
*      Parameters:
*          input: the base64 encoded string to be measured

```

```

*           inputLen: the length of the base64 encoded string
*           Return value:
*           Returns the length of the decoded form of a
*           base64 encoded string
*           Requirements:
*           1. input must not be null
*           2. input must be greater than or equal to zero
*/
int base64_dec_len(char *input, int inputLen);

#endif // _BASE64_H

```

app_httpd.cpp

```

#include "dl_lib_matrix3d.h" //Para convertir fotos en redes neuronales (reconocimiento facial
#include <esp32-hal-ledc.h> //configura canales PWM
int speed = 255;
int noStop = 0;

#include "esp_http_server.h"
#include "esp_timer.h"
#include "esp_camera.h"
#include "img_converters.h"
#include "Arduino.h"
#include <WiFiClientSecure.h>
#include "Base64.h"

//---> Para Guardar en Google Driver
String myScript = "/macros/s/AKfycbxtKpxBMKo...../exec"; // sustituir
const char* myDomain = "script.google.com";
String myFilename = "filename=ESP32-CAM.jpg";
String mimeType = "&mimetype=image/jpeg";
String myImage = "&data=";

int waitingTime = 30000; //Wait 30 seconds to google response.

//--->Definición de funciones
String Photo2Base64();
String urlencode(String str);
void saveCapturedImage();

//define estructura de datos para la foto
typedef struct {
    httpd_req_t *req;
    size_t len;
} jpg_chunking_t;

#define PART_BOUNDARY "12345678900000000000000987654321"
static const char* _STREAM_CONTENT_TYPE = "multipart/x-mixed-replace;boundary=" PART_BOUNDARY;
//BOUNDARY=PERÍMETRO
static const char* _STREAM_BOUNDARY = "\r\n--" PART_BOUNDARY "\r\n";
static const char* _STREAM_PART = "Content-Type: image/jpeg\r\nContent-Length: %u\r\n\r\n";

//.....
httpd_handle_t stream_httpd = NULL;
httpd_handle_t camera_httpd = NULL;
//.....
static size_t jpg_encode_stream(void * arg, size_t index, const void* data, size_t len){
    jpg_chunking_t *j = (jpg_chunking_t *)arg;

```



```

if(!index){
    j->len = 0;
}
if(httpd_resp_send_chunk(j->req, (const char *)data, len) != ESP_OK){
    return 0;
}
j->len += len;
return len;
}
//..... HACE FOTO .....
static esp_err_t capture_handler(httpd_req_t *req){

    camera_fb_t * fb = NULL;
    esp_err_t res = ESP_OK;
    int64_t fr_start = esp_timer_get_time();

    fb = esp_camera_fb_get();
    if (!fb) {
        Serial.println("Camara captura fallida");
        httpd_resp_send_500(req);
        return ESP_FAIL;
    }

    httpd_resp_set_type(req, "image/jpeg");
    httpd_resp_set_hdr(req, "Content-Disposition", "inline; filename=capture.jpg");

    size_t out_len, out_width, out_height;
    uint8_t * out_buf;
    bool s;
    {
        size_t fb_len = 0;
        if(fb->format == PIXFORMAT_JPEG){
            fb_len = fb->len;
            res = httpd_resp_send(req, (const char *)fb->buf, fb->len);
        } else {
            jpg_chunking_t jchunk = {req, 0};
            res = frame2jpg_cb(fb, 80, jpg_encode_stream, &jchunk)?ESP_OK:ESP_FAIL;
            httpd_resp_send_chunk(req, NULL, 0);
            fb_len = jchunk.len;
        }
        esp_camera_fb_return(fb);
        int64_t fr_end = esp_timer_get_time();
        Serial.printf("JPG: %uB %ums\n", (uint32_t)(fb_len), (uint32_t)((fr_end - fr_start)/1000));
        Serial.println("Guarda foto en driver");
        saveCapturedImage(); //Guarda foto en driver
        return res;
    }

    dl_matrix3du_t *image_matrix = dl_matrix3du_alloc(1, fb->width, fb->height, 3);
    if (!image_matrix) {
        esp_camera_fb_return(fb);
        Serial.println("dl_matrix3du_alloc failed");
        httpd_resp_send_500(req);
        return ESP_FAIL;
    }

    out_buf = image_matrix->item;
    out_len = fb->width * fb->height * 3;
    out_width = fb->width;
    out_height = fb->height;

    s = fmt2rgb888(fb->buf, fb->len, fb->format, out_buf);
    esp_camera_fb_return(fb);
    if(!s){
        dl_matrix3du_free(image_matrix);
        Serial.println("to rgb888 failed");
        httpd_resp_send_500(req);
    }
}

```

```

    return ESP_FAIL;
}

jpg_chunking_t jchunk = {req, 0};
s = fmt2jpg_cb(out_buf, out_len, out_width, out_height, PIXFORMAT_RGB888, 90, jpg_encode_stream, &jchunk);
dl_matrix3du_free(image_matrix);
if(!s){
    Serial.println("JPEG compression failed");
    return ESP_FAIL;
}

int64_t fr_end = esp_timer_get_time();

return res;
}
//..... VIDEO .....
static esp_err_t stream_handler(httpd_req_t *req){

    camera_fb_t *fb = NULL;
    esp_err_t res = ESP_OK;
    size_t _jpg_buf_len = 0;
    uint8_t * _jpg_buf = NULL;
    char * part_buf[64];
    dl_matrix3du_t *image_matrix = NULL;

    static int64_t last_frame = 0;
    if(!last_frame) {
        last_frame = esp_timer_get_time();
    }

    res = httpd_resp_set_type(req, _STREAM_CONTENT_TYPE);
    if(res != ESP_OK){
        return res;
    }

    while(true){
        fb = esp_camera_fb_get();
        if (!fb) {
            Serial.println("Camera capture failed");
            res = ESP_FAIL;
        } else {
            {
                if(fb->format != PIXFORMAT_JPEG){
                    bool jpeg_converted = frame2jpg(fb, 80, &_jpg_buf, &_jpg_buf_len);
                    esp_camera_fb_return(fb);
                    fb = NULL;
                    if(!jpeg_converted){
                        Serial.println("JPEG compression failed");
                        res = ESP_FAIL;
                    }
                } else {
                    _jpg_buf_len = fb->len;
                    _jpg_buf = fb->buf;
                }
            }
        }
        if(res == ESP_OK){
            size_t hlen = snprintf((char *)part_buf, 64, _STREAM_PART, _jpg_buf_len);
            res = httpd_resp_send_chunk(req, (const char *)part_buf, hlen);
        }
        if(res == ESP_OK){
            res = httpd_resp_send_chunk(req, (const char *)_jpg_buf, _jpg_buf_len);
        }
        if(res == ESP_OK){
            res = httpd_resp_send_chunk(req, _STREAM_BOUNDARY, strlen(_STREAM_BOUNDARY));
        }
        if(fb){
            esp_camera_fb_return(fb);

```

```

        fb = NULL;
        _jpg_buf = NULL;
    } else if(!_jpg_buf){
        free(_jpg_buf);
        _jpg_buf = NULL;
    }
    if(res != ESP_OK){
        break;
    }
    int64_t fr_end = esp_timer_get_time();
    int64_t frame_time = fr_end - last_frame;
    last_frame = fr_end;
    frame_time /= 1000;
    Serial.printf("MJPG: %uB %ums (%.1ffps)\n",
        (uint32_t)(_jpg_buf_len),
        (uint32_t)frame_time, 1000.0 / (uint32_t)frame_time
    );
}

last_frame = 0;
return res;
}

//..... CONTROLES (BOTONES Y DESLIZADORES).....
enum state {fwd,rev,stp,drv};
state actstate = stp;

static esp_err_t cmd_handler(httpd_req_t *req)
{
    char* buf;
    size_t buf_len;
    char variable[32] = {0,};
    char value[32] = {0,};

    buf_len = httpd_req_get_url_query_len(req) + 1;
    if (buf_len > 1) {
        buf = (char*)malloc(buf_len);
        if(!buf){
            httpd_resp_send_500(req);
            return ESP_FAIL;
        }
        if (httpd_req_get_url_query_str(req, buf, buf_len) == ESP_OK) {
            if (httpd_query_key_value(buf, "var", variable, sizeof(variable)) == ESP_OK &&
                httpd_query_key_value(buf, "val", value, sizeof(value)) == ESP_OK) {
            } else {
                free(buf);
                httpd_resp_send_404(req);
                return ESP_FAIL;
            }
        } else {
            free(buf);
            httpd_resp_send_404(req);
            return ESP_FAIL;
        }
    } else {
        free(buf);
    }
    httpd_resp_send_404(req);
    return ESP_FAIL;
}

int val = atoi(value);
sensor_t * s = esp_camera_sensor_get();
int res = 0;

if(!strcmp(variable, "framesize")) {
    Serial.println("framesize");
    if(s->pixformat == PIXFORMAT_JPEG) res = s->set_framesize(s, (framesize_t)val);
}
else if(!strcmp(variable, "quality")) {

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    Serial.println("quality");
    res = s->set_quality(s, val);
}
//***** Controles *****//
//No use el canal 1 y el canal 2
else if(!strcmp(variable, "flash")) {
    ledcWrite(7,val); // Led flash
}
else if(!strcmp(variable, "speed")) {
    if (val > 255) val = 255;
    else if (val < 0) val = 0;
    speed = val;
}
else if(!strcmp(variable, "nostop")) {
    noStop = val;
}
else if(!strcmp(variable, "servo")){ // 3250, 4875, 6500
    if (val > 650) val = 650; //650
    else if (val < 325) val = 325; //325
    ledcWrite(8,10*val); //servo
}
else if(!strcmp(variable, "car")) {

    if (val==1) {
        Serial.println("Adelante");
        actstate = fwd;
        ledcWrite(3,speed);
        ledcWrite(4,0);
        ledcWrite(5,speed);
        ledcWrite(6,0);
        delay(200);
    }
    else if (val==2) {
        Serial.println("Giro izquierdas");
        ledcWrite(4,255);
        ledcWrite(6,0);

        //if (actstate == fwd) { ledcWrite(4,speed); ledcWrite(6, 0); }
        //else if (actstate == rev) { ledcWrite(4, 0); ledcWrite(6,speed); }
        //else { ledcWrite(4,speed); ledcWrite(6,speed); }
        ledcWrite(3,speed);
        ledcWrite(5,speed);

        delay(300);
        ledcWrite(3,0);
        ledcWrite(5,0);
    }
    else if (val==3) {
        Serial.println("Parar");
        actstate = stp;
        ledcWrite(4,0);
        ledcWrite(3,0);
        ledcWrite(5,0);
        ledcWrite(6,0);
    }
    else if (val==4) {
        Serial.println("Giro derecha");
        ledcWrite(4,0);
        ledcWrite(6,255);

        //if (actstate == fwd) { ledcWrite(3, 0); ledcWrite(5,speed); }
        //else if (actstate == rev) { ledcWrite(3,speed); ledcWrite(5, 0); }
        //else { ledcWrite(3,speed); ledcWrite(5,speed); }
        ledcWrite(3,speed);
        ledcWrite(5,speed);

        delay(300);
    }
}

```

```

    ledcWrite(3, 0);
    ledcWrite(5, 0);

}
else if (val==5) {
    Serial.println("Atrás");
    actstate = rev;
    ledcWrite(3,speed); // pin 12
    ledcWrite(4,255);    // pin 13
    ledcWrite(5,speed); // pin 14
    ledcWrite(6,255);    // pin 15

    delay(200);
}
else if (val==6) {
    Serial.println("Guarda foto en driver");
    actstate = drv;
    saveCapturedImage();
    delay(200);
}

if (noStop!=1) {
    ledcWrite(3, 0);
    ledcWrite(4, 0);
    ledcWrite(5, 0);
    ledcWrite(6, 0);
    depurar("Manual");
}
} //if car
else {
    Serial.println("variable");
    res = -1;
} //else car

if(res){ return httpd_resp_send_500(req); }

httpd_resp_set_hdr(req, "Access-Control-Allow-Origin", "");
return httpd_resp_send(req, NULL, 0);
}
//.....
static esp_err_t status_handler(httpd_req_t *req){
    static char json_response[1024];
    Serial.println("-----");
    Serial.println("status_handler");
    sensor_t * s = esp_camera_sensor_get();
    char * p = json_response;
    *p++ = '{';

    p+=sprintf(p, "\"framesize\":%u,", s->status.framesize);
    p+=sprintf(p, "\"quality\":%u,", s->status.quality);
    *p++ = '}';
    *p++ = 0;
    httpd_resp_set_type(req, "application/json");
    httpd_resp_set_hdr(req, "Access-Control-Allow-Origin", "");
    return httpd_resp_send(req, json_response, strlen(json_response));
}
//.....
// Pagina Web
static const char PROGMEM INDEX_HTML[] = R"rawliteral(
<!doctype html>
<html>
<head>
    <meta charset="utf-8">
    <meta name="viewport" content="width=device-width,initial-scale=1">
    <title>Coche con ESP32 OV2460 </title>
    <style>

```

```

body{font-family:Arial,Helvetica,sans-serif;background:#181818;color:#EFEFEF;font-size:16px}h2{font-size:18px}section.
main{display:flex}#menu,section.main{flex-direction:column}#menu{display:none;flex-wrap:nowrap;min-width:340px;back
ground:#363636;padding:8px;border-radius:4px;margin-top:-10px;margin-right:10px}#content{display:flex;flex-wrap:wrap;
align-items:stretch}figure{padding:0;margin:0;-webkit-margin-before:0;margin-block-start:0;-webkit-margin-after:0;margin-
block-end:0;-webkit-margin-start:0;margin-inline-start:0;-webkit-margin-end:0;margin-inline-end:0}figure
img{display:block;width:100%;height:auto;border-radius:4px;margin-top:8px}@media (min-width: 800px) and
(orientation:landscape){#content{display:flex;flex-wrap:nowrap;align-items:stretch}figure
img{display:block;max-width:100%;max-height:calc(100vh -
40px);width:auto;height:auto}figure{padding:0;margin:0;-webkit-margin-before:0;margin-block-start:0;-webkit-margin-after:
0;margin-block-end:0;-webkit-margin-start:0;margin-inline-start:0;-webkit-margin-end:0;margin-inline-end:0}}section#butto
ns{display:flex;flex-wrap:nowrap;justify-content:space-between}#nav-toggle{cursor:pointer;display:block}#nav-toggle-cb{o
utline:0;opacity:0;width:0;height:0}#nav-toggle-cb:checked+#menu{display:flex}.input-group{display:flex;flex-wrap:nowrap
;line-height:22px;margin:5px 0}.input-group>label{display:inline-block;padding-right:10px;min-width:47%}.input-group
input,.input-group select{flex-grow:1}.range-max,.range-min{display:inline-block;padding:0
5px}button{display:block;margin:5px;padding:0
12px;border:0;line-height:28px;cursor:pointer;color:#fff;background:#ff3034;border-radius:5px;font-size:16px;outline:0}but
ton:hover{background:#ff494d}button:active{background:#f21c21}button.disabled{cursor:default;background:#a0a0a0}inp
ut[type=range]{-webkit-appearance:none;width:100%;height:22px;background:#363636;cursor:pointer;margin:0}input[typ
e=range]:focus{outline:0}input[type=range]::-webkit-slider-runnable-track{width:100%;height:2px;cursor:pointer;backgrou
nd:#EFEFEF;border-radius:0;border:0 solid #EFEFEF}input[type=range]::-webkit-slider-thumb{border:1px solid
rgba(0,0,30,0);height:22px;width:22px;border-radius:50px;background:#ff3034;cursor:pointer;-webkit-appearance:none;m
argin-top:-11.5px}input[type=range]:focus::-webkit-slider-runnable-track{background:#EFEFEF}input[type=range]::-moz-ra
nge-track{width:100%;height:2px;cursor:pointer;background:#EFEFEF;border-radius:0;border:0 solid
#EFEFEF}input[type=range]::-moz-range-thumb{border:1px solid
rgba(0,0,30,0);height:22px;width:22px;border-radius:50px;background:#ff3034;cursor:pointer}input[type=range]::-ms-trac
k{width:100%;height:2px;cursor:pointer;background:0
0;border-color:transparent;color:transparent}input[type=range]::-ms-fill-lower{background:#EFEFEF;border:0 solid
#EFEFEF;border-radius:0}input[type=range]::-ms-fill-upper{background:#EFEFEF;border:0 solid
#EFEFEF;border-radius:0}input[type=range]::-ms-thumb{border:1px solid
rgba(0,0,30,0);height:22px;width:22px;border-radius:50px;background:#ff3034;cursor:pointer;height:2px}input[type=range
]:focus::-ms-fill-lower{background:#EFEFEF}input[type=range]:focus::-ms-fill-upper{background:#363636}.switch{display:
block;position:relative;line-height:22px;font-size:16px;height:22px}.switch
input{outline:0;opacity:0;width:0;height:0}.slider{width:50px;height:22px;border-radius:22px;cursor:pointer;background-col
or:grey}.slider,.slider:before{display:inline-block;transition:.4s}.slider:before{position:relative;content:"";border-radius:50%;
height:16px;width:16px;left:4px;top:3px;background-color:#fff}input:checked+.slider{background-color:#ff3034}input:check
ed+.slider:before{-webkit-transform:translateX(26px);transform:translateX(26px)}select{border:1px solid
#363636;font-size:14px;height:22px;outline:0;border-radius:5px}.image-container{position:relative;min-width:160px}.close
{position:absolute;right:5px;top:5px;background:#ff3034;width:16px;height:16px;border-radius:100px;color:#fff;text-align:c
enter;line-height:18px;cursor:pointer}.hidden{display:none}
</style>
</head>
<body>
<figure>
<div id="stream-container" class="image-container hidden">
<div class="close" id="close-stream">x</div>
<img id="stream" src="">
</div>
</figure>
<section class="main" align="center">
<section id="buttons">
<table>
<tr>
<td align="center">
<button id="get-still">Guardar Foto</button>
</td>
<td></td>
<td align="center">
<button id="toggle-stream">Camara </button>
</td>
</tr>
<tr>
<td>
<input type="checkbox" id="nostop" onclick="var noStop=0;if (this.checked)
noStop=1;fetch(document.location.origin+'/control?var=nostop&val='+noStop);">No Stop
</td>
<td align="center">
<button id="forward" onclick="fetch(document.location.origin+'/control?var=car&val=1');">Adelante</button>
</td>

```

```

        <td></td>
    </tr>
    <tr>
        <td align="center">
            <button id="turnleft" onclick="fetch(document.location.origin+'/control?var=car&val=2');">Izquierda</button>
        </td>
        <td align="center">
            <button id="stop" onclick="fetch(document.location.origin+'/control?var=car&val=3');">Stop</button>
        </td>
        <td align="center">
            <button id="turnright" onclick="fetch(document.location.origin+'/control?var=car&val=4');">Derecha</button>
        </td>
    </tr>
    <tr>
        <td></td>
        <td align="center">
            <button id="backward" onclick="fetch(document.location.origin+'/control?var=car&val=5');">Atras</button>
        </td>
        <td></td>
    </tr>
    <tr>
        <td></td>
        <td align="center">
            <button id="Gfoto" onclick="fetch(document.location.origin+'/control?var=car&val=6');">Guardar foto</button>
        </td>
        <td></td>
    </tr>
    <tr>
        <td></td>
        <td align="center" colspan="2">
            <input type="range" id="flash" min="0" max="255" value="0"
            onchange="try{fetch(document.location.origin+'/control?var=flash&val='+this.value);}catch(e){}">
        </td>
    </tr>
    <tr>
        <td></td>
        <td align="center" colspan="2">
            <input type="range" id="speed" min="0" max="255" value="255"
            onchange="try{fetch(document.location.origin+'/control?var=speed&val='+this.value);}catch(e){}">
        </td>
    </tr>
    <tr>
        <td></td>
        <td align="center" colspan="2">
            <input type="range" id="servo" min="325" max="650" value="487"
            onchange="try{fetch(document.location.origin+'/control?var=servo&val='+this.value);}catch(e){}">
        </td>
    </tr>
    <tr>
        <td></td>
        <td align="center" colspan="2">
            <input type="range" id="quality" min="10" max="63" value="10"
            onchange="try{fetch(document.location.origin+'/control?var=quality&val='+this.value);}catch(e){}">
        </td>
    </tr>
    <tr>
        <td></td>
        <td align="center" colspan="2">
            <input type="range" id="framesize" min="0" max="6" value="5"
            onchange="try{fetch(document.location.origin+'/control?var=framesize&val='+this.value);}catch(e){}">
        </td>
    </tr>
    </table>
</section>
</section>
<script>
    document.addEventListener('DOMContentLoaded',function(){function b(B){let
    C;switch(B.type){case'checkbox':C=B.checked?1:0;break;case'range':case'select-one':C=B.value;break;case'button':case
    'submit':C=1;break;default:return;}const D=`${C}/control?var=${B.id}&val=${C}`;fetch(D).then(E=>{console.log(' request to
    ${D} finished, status: ${E.status}')})}var c=document.location.origin;const
    e=B=>{B.classList.add('hidden')},f=B=>{B.classList.remove('hidden')},g=B=>{B.classList.add('disabled'),B.disabled=!0},h=
    B=>{B.classList.remove('disabled'),B.disabled=!1},i=(B,C,D)=>{D!=(null!=D)}||D;let
    E;'checkbox'===B.type?(E=B.checked,C=!C,B.checked=C):(E=B.value,B.value=C),D&&E!==(C?b(B):!D&&('aec'===B.id?

```

```

C?e(v):f(v):'agc'===B.id?C?(f(t),e(s)):(e(t),f(s)):'awb_gain'===B.id?C?f(x):e(x):'face_recognize'===B.id&&(C?h(n):g(n)));document.querySelectorAll('.close').forEach(B=>{B.onclick=()=>{e(B.parentNode)}},fetch(`${c}/status`).then(function(B){return B.json()}).then(function(B){document.querySelectorAll('.default-action').forEach(C=>{i(C,B[C.id],!1)}));const j=document.getElementById('stream'),k=document.getElementById('stream-container'),l=document.getElementById('get-still'),m=document.getElementById('toggle-stream'),n=document.getElementById('face_enroll'),o=document.getElementById('close-stream'),p=()=>{window.stop(),m.innerHTML='Start Stream'},q=()=>{j.src=`${c+':81'}/stream`,f(k),m.innerHTML='Stop Stream'},l.onclick=()=>{p(),j.src=`${c}/capture?_cb=${Date.now()}`,f(k)},o.onclick=()=>{p(),e(k)},m.onclick=()=>{const B='Stop Stream'===m.innerHTML;B?p():q(),n.onclick=()=>{b(n)},document.querySelectorAll('.default-action').forEach(B=>{B. onchange=()=>b(B)});const r=document.getElementById('agc'),s=document.getElementById('agc_gain-group'),t=document.getElementById('gainceiling-group');r.onchange=()=>{b(r),r.checked?(f(t),e(s)):(e(t),f(s))};const u=document.getElementById('aec'),v=document.getElementById('aec_value-group');u.onchange=()=>{b(u),u.checked?e(v):f(v)};const w=document.getElementById('awb_gain'),x=document.getElementById('wb_mode-group');w.onchange=()=>{b(w),w.checked?f(x):e(x)};const y=document.getElementById('face_detect'),z=document.getElementById('face_recognize'),A=document.getElementById('framesize');A.onchange=()=>{b(A),5<A.value&&(i(y,!1),i(z,!1))},y.onchange=()=>{return 5<A.value?(alert('Please select CIF or lower resolution before enabling this feature!'),void i(y,!1)):void(b(y),!y.checked&&(g(n),i(z,!1)))},z.onchange=()=>{return 5<A.value?(alert('Please select CIF or lower resolution before enabling this feature!'),void i(z,!1)):void(b(z),z.checked?(h(n),i(y,!0)):g(n))}});
</script>
</body>
</html>
)rawliteral";
//.....
static esp_err_t index_handler(httpd_req_t *req){
    Serial.println("-----");
    Serial.println("index_handler");
    httpd_resp_set_type(req, "text/html");
    return httpd_resp_send(req, (const char *)INDEX_HTML, strlen(INDEX_HTML));
}

//.....

void startCameraServer()
{
    Serial.println("-----");
    Serial.println("startCameraServer");
    httpd_config_t config = HTTPD_DEFAULT_CONFIG();

    httpd_uri_t index_uri = {
        .uri      = "/",
        .method    = HTTP_GET,
        .handler   = index_handler,
        .user_ctx  = NULL
    };

    httpd_uri_t status_uri = {
        .uri      = "/status",
        .method    = HTTP_GET,
        .handler   = status_handler,
        .user_ctx  = NULL
    };

    httpd_uri_t cmd_uri = {
        .uri      = "/control",
        .method    = HTTP_GET,
        .handler   = cmd_handler,
        .user_ctx  = NULL
    };

    httpd_uri_t capture_uri = {
        .uri      = "/capture",
        .method    = HTTP_GET,
        .handler   = capture_handler,
        .user_ctx  = NULL
    };

```



```

};

httpd_uri_t stream_uri = {
    .uri      = "/stream",
    .method   = HTTP_GET,
    .handler  = stream_handler,
    .user_ctx = NULL
};

Serial.printf("Starting web server on port: %d\n", config.server_port);
if (httpd_start(&camera_httpd, &config) == ESP_OK) {
    httpd_register_uri_handler(camera_httpd, &index_uri);
    httpd_register_uri_handler(camera_httpd, &cmd_uri);
    httpd_register_uri_handler(camera_httpd, &status_uri);
    httpd_register_uri_handler(camera_httpd, &capture_uri);
}

config.server_port += 1;
config.ctrl_port += 1;
Serial.printf("Starting stream server on port: %d\n", config.server_port);
if (httpd_start(&stream_httpd, &config) == ESP_OK) {
    httpd_register_uri_handler(stream_httpd, &stream_uri);
}
} //star camara
//.....

//Foto a driver
void saveCapturedImage() {
    // Serial.println("Connect to " + String(myDomain));
    WiFiClientSecure client;

    if (client.connect(myDomain, 443)) {
        Serial.println("Connection successful");

        camera_fb_t * fb = NULL;
        fb = esp_camera_fb_get();
        if(!fb) {
            Serial.println("Camera capture failed");
            delay(1000);
            ESP.restart();
            return;
        }

        char *input = (char *)fb->buf;
        char output[base64_enc_len(3)];
        String imageFile = "";
        for (int i=0;i<fb->len;i++) {
            base64_encode(output, (input++), 3);
            if (i%3==0) imageFile += urlencode(String(output));
        }
        String Data = myFilename+mimeType+myImage;

        esp_camera_fb_return(fb);

        Serial.println("Send a captured image to Google Drive.");

        client.println("POST " + myScript + " HTTP/1.1");
        client.println("Host: " + String(myDomain));
        client.println("Content-Length: " + String(Data.length()+imageFile.length()));
        client.println("Content-Type: application/x-www-form-urlencoded");
        client.println();

        client.print(Data);
        int Index;
        for (Index = 0; Index < imageFile.length(); Index = Index+1000) {
            client.print(imageFile.substring(Index, Index+1000));
        }
    }
}

```

```

Serial.println("Waiting for response.");
long int StartTime=millis();
while (!client.available()) {
    Serial.print(".");
    delay(100);
    if ((StartTime+waitingTime) < millis()) {
        Serial.println();
        Serial.println("No response.");
        //If you have no response, maybe need a greater value of waitingTime
        break;
    }
}
Serial.println();
while (client.available()) {
    Serial.print(char(client.read()));
}
} else {
    Serial.println("Connected to " + String(myDomain) + " failed.");
}
client.stop();
}

```

```

String Photo2Base64() {
    camera_fb_t * fb = NULL;
    fb = esp_camera_fb_get();
    if(!fb) {
        Serial.println("Camera capture failed");
        return "";
    }

    String imageFile = "data:image/jpeg;base64,";
    char *input = (char *)fb->buf;
    char output[base64_enc_len(3)];
    for (int i=0;i<fb->len;i++) {
        base64_encode(output, (input++), 3);
        if (i%3==0) imageFile += urlencode(String(output));
    }

    esp_camera_fb_return(fb);

    return imageFile;
}

```

```

//https://github.com/zenmanenergy/ESP8266-Arduino-Examples/
String urlencode(String str)
{
    String encodedString="";
    char c;
    char code0;
    char code1;
    char code2;
    for (int i =0; i < str.length(); i++){
        c=str.charAt(i);
        if (c == ' '){
            encodedString+= '+';
        } else if (isalnum(c)){
            encodedString+=c;
        } else{
            code1=(c & 0xf)+'0';
            if ((c & 0xf) >9){
                code1=(c & 0xf) - 10 + 'A';
            }
            c=(c>>4)&0xf;
            code0=c+'0';
            if (c > 9){
                code0=c - 10 + 'A';
            }
        }
    }
}

```

```

    code2='\0';
    encodedString+='%';
    encodedString+=code0;
    encodedString+=code1;
    //encodedString+=code2;
  }
  yield();
}
return encodedString;
}

// Publica dato y muestra en el terminal
void publica( String dato_publicar){ // Publica dato
  Serial.println(dato_publicar);
}

```

Pines del ES32-CAM:

Funcionamiento de los motores:

speed: valor del canal obtenido por el deslizador velocidad de la página Web (0 a 255).

Pines Arduino Motor Shield	Pines ESP32 (control manual)	Canal	Paro	Avanza	Retrocede	Giro Izq.	Giro Der.
D3 (MA on/off)	IO12	3	0	speed	speed	speed	speed
D12 (MA dir)	IO13	4	0	0	255	255	0
D11 (MB on/off)	IO14	5	0	speed	speed	speed	speed
D13 (MB dir)	IO15	6	0	0	255	0	255

Información:

Proyecto:

<https://github.com/alfajor144/ESP32-proyectos/tree/master/ESP32CAM>

Camara subir fotos FTP

<https://www.gsampallo.com/2020/04/20/subir-fotos-a-un-servidor-ftp-con-esp32-cam/>

Generar PWM

<https://randomnerdtutorials.com/esp32-pwm-arduino-ide/>

Camara subir fotos a Google Diver

https://github.com/raphaelbs/esp32-cam-ai-thinker/tree/master/examples/google_storage

Arduino Motor Shield

<https://store.arduino.cc/arduino-motor-shield-rev3>

Fotos:

