```cpp
// drive.hpp: Header file for utilities relating to the drive
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//
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#pragma once
#include "motors.hpp"
#include "sensors.hpp"

/** Contains everything relating to the drive */
namespace drive {
  /** Class for a side of the drive */
  struct side_t {
    /** Top motor on the the side */
    motor_t topM;
    /** Middle motor on the side */
    motor_t midM;
    /** Bottom motor on the side */
    motor_t lowM;
    /** Sets all motors on the side to the given power */
    void set(int power);
    /** A pointer to the sensor on the side */
    sensors::quad_t* sensor;
  }; // struct side_t

  /** Multiplier for which 1 inch is used to convert into degreees rotation on
   * 4"
   * wheels */
  extern double inch;
  /** The left side of the drive */
  extern side_t left;
  /** The right side of the drive */
  extern side_t right;

  /** Set both sides of the drive at their requested powers */
```

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  void set(int lpower, int rpower);

  /** Initialize the drive subsystem */
  void init(void);

  /** Drive a specific number of inches */
  void inches(long inches);

  /** Tank control that should be used in a while loop */
  void tank(void);

  /** Joystick accelerometer driving! */
  namespace accel {
    /** Current x value of the joystick accel */
    extern int x;
    /** Current y value of the joystick accel */
    extern int y;
    /** Previous joystick accel x value */
    extern int prevX;
    /** Previous joystick accel y value */
    extern int prevY;

    /** Tilt control using the josytick accelerometer. Should be used in a while
     * loop */
    void drive(void);
  } // namespace accel
} // namespace drive
```