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// motors.cpp: Source file of hardware abstraction for motors and slewing
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#include "../include/motors.hpp"

void motor_t::set(int _power) {
    power = motors::slew::list[port].power = _power * inverted * scale;
}

namespace motors {
    void set(motor_t motor, int power) {
        motor.set(power);
    }

    int get(motor_t motor) {
        return motor.power;
    }

    motor_t init(unsigned char port, int inverted, float slewRate, float scale) {
        motor_t motor;
        motor.port = port;
        motor.inverted = inverted;
        motor.slewRate = slewRate;
        motor.scale = scale;
        slew::list[motor.port] = motor;
        return motor;
    }

    namespace slew {
        motor_t list[11];
        TaskHandle handle;

        void _slew(void* none) {

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    unsigned long int current;
    while (true) {
        current = millis();
        for (size_t i = 1; i <= 10; i++) {
            motorSet(i,
                (int)((list[i].power - motorGet(i)) * list[i].slewRate) +
                    ((list[i].power >= motorGet(i))
                        ? (current - list[i].tlast - slewWait)
                        : (-1 * (current - list[i].tlast - slewWait))) +
                    motorGet(i)));
            list[i].tlast = current;
        }
        delay(slewWait);
    }
    free(none);
}

void init(void) {
    motor_t default_motor;
    default_motor.inverted = 1;
    default_motor.slewRate = 1;
    default_motor.scale = 0;
    for (size_t i = 1; i <= 11; i++) {
        list[i] = default_motor;
        default_motor.port = i;
    }
    handle = taskCreate(&_slew, TASK_DEFAULT_STACK_SIZE, NULL,
        TASK_PRIORITY_DEFAULT + 1);
}
} // namespace slew
} // namespace motors

```