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// drive.cpp: Source file for utilities relating to the drive
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//
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#include "../include/main.h"

namespace drive {
    side_t left;
    side_t right;
    double inch =
        28.64788975654116043839907740705258516620273623328216077458012735;

    void side_t::set(int power) {
        side_t::topM.set(power);
        side_t::midM.set(power);
        side_t::lowM.set(power);
    }

    void init(void) {
        left.topM = motors::init(2, 1, .5, .8);
        left.midM = motors::init(3, -1, .5, .8);
        left.lowM = motors::init(4, 1, .5, .8);
        right.topM = motors::init(7, -1, .5, .8);
        right.midM = motors::init(8, 1, .5, .8);
        right.lowM = motors::init(9, -1, .5, .8);
        left.sensor = &sensors::left;
        right.sensor = &sensors::right;
    }

    void set(int lpower, int rpower) {
        left.set(lpower);
        right.set(rpower);
    }
}

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void tank(void) {
    int deadband = 20;
    int lj      = joystickGetAnalog(1, 3);
    int rj      = joystickGetAnalog(1, 2);
    if (abs(lj) < deadband && abs(rj) < deadband) {
        pid::enable();
        return;
    }
    lj          = (abs(lj) < deadband) ? 0 : lj;
    rj          = (abs(rj) < deadband) ? 0 : rj;
    pid::enabled[0] = (lj == 0);
    pid::enabled[1] = (rj == 0);
    if (lj != 0)
        left.set(lj);
    if (rj != 0)
        right.set(rj);
    pid::request((lj == 0) ? left.sensor->request : left.sensor->value(),
                 (rj == 0) ? right.sensor->request : right.sensor->value());
}

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namespace accel {
    int deadband = 20;
    int x        = 0;
    int y        = 0;
    int prevX    = 0;
    int prevY    = 0;
    void drive(void) {
        prevX      = x;
        prevY      = y;
        x          = 0 - joystickGetAnalog(1, ACCEL_X);
        y          = 0 - joystickGetAnalog(1, ACCEL_Y);
        int threshold = 20;
        double multiplier = 1.1;

        if (abs(x) < threshold)
            x = 0;
        if (abs(y) < threshold)
            y = 0;

        x *= multiplier;
        y *= (multiplier * 1.25);

        int lj      = x - y;
        int rj      = x + y;
        lj          = (abs(lj) < deadband) ? 0 : lj;
        rj          = (abs(rj) < deadband) ? 0 : rj;
    }
}

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    pid::enabled[0] = (lj == 0);
    pid::enabled[1] = (rj == 0);
    if (lj != 0)
        left.set(lj);
    if (rj != 0)
        right.set(rj);
    pid::request((lj == 0) ? left.sensor->request : left.sensor->value(),
                 (rj == 0) ? right.sensor->request : right.sensor->value());
}
} // namespace accel

void inches(long inches) {
    pid::enable();
    left.sensor->request += inches * inch;
    right.sensor->request += inches * inch;
    pid::wait(pid::default_precision, inches * inches * 8);
    pid::disable();
}

namespace gyro {
    void drive::task(void* none) {
        float change[2] = {0};
        while (on) {
            changer = (abs(gyro->value() - iHeading) - tolerance) * urgency;
            if (gyro->value() > iHeading + tolerance) {
                change[0] -= changer;
                change[1] += changer;
            } else if (gyro->value() < iHeading - tolerance) {
                change[0] += changer;
                change[1] -= changer;
            }
            pid::request(change[0], change[1]);
            delay(50);
        }
    }

    void drive::off(void) {
        on = false;
    }

    drive::drive(int heading, float urgency, bool absolute,
                 sensors::gyro_t* gyro, unsigned int tolerance)
        : heading(heading),
          urgency(urgency),
          gyro(gyro),
          iHeading(absolute ? heading : heading + gyro->value()) {}

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    }  
  } // namespace gyro  
} // namespace drive
```