

```
1 #ifndef _DRIVE_
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3
4 #define WHEELDIM 4_in
5 #define WHEELTRACK 10_in
6
7 #include "main.h"
8 #include "ports.h"
9
10 //chassis controller wrapper with drive utilities
11 class Drive {
12 private:
13     std::shared_ptr<okapi::OdomChassisController> chassis;
14     // okapi::IntegratedEncoder enc;
15     int speedfactor;
16 public:
17     Drive();
18     double getX();
19     double getY();
20     double getHeading();
21     void run(double forward, double strafe, double turn);
22     okapi::OdomState getState();
23     void runWithController();
24     void runTankArcade(double forward, double turn);
25     void runTank(double left, double right);
26     void reverseOrientation(int ori);
27     void setMode(okapi::AbstractMotor::brakeMode brakeMode);
28     // double getEncoder();
29 };
30
31 #endif
```