

```
1 #ifndef _INTAKE_
2 #define _INTAKE_
3
4 #include "main.h"
5
6
7 //Class for intake and four bar actuation
8 class Intake {
9 private:
10     okapi::Motor m;
11     bool dir;
12     bool moving;
13     std::vector<int> encPositions;
14     int prevCount = 0;
15     int upper;
16     int lower;
17     bool limits = false;
18 public:
19     Intake(double port);
20     void run(bool left, bool right, double speed);
21     void moveTarget(double enc);
22     void setTarget(double enc);
23     void stepAbsolute(int count, double speed);
24     void addPosition(int pos);
25     void step();
26     void setLimits(int upper, int lower);
27     void handle(int count, double speed);
28 };
29
30
31
32 #endif
```