

```

#include "main.h"

void operatorControl() {
    mutexTake(runFingerMutex, -1);
    runFinger = false;
    mutexGive(runFingerMutex);

    mutexTake(runLiftMutex, -1);
    runLift = false;
    mutexGive(runLiftMutex);

    mutexTake(runWheelsMutex, -1);
    runWheels = false;
    mutexGive(runWheelsMutex);

    autonSelection = programSelected(8);

    int lastTime = millis();
    while (1) {
        autonSelection = programSelected(8);

        if(millis() - lastTime > 100){
            lastTime = millis();
            lcdPrint(uart1, 1, "%d,%d", gyroGet(gyroOne), gyroGet(gyroTwo));
            lcdPrint(uart1, 2, "%d,%d", abs((gyroGet(gyroOne) + gyroGet(gyroTwo))) / 2, autonSelection);
        }

        int liftPotValue = analogRead(liftPot);
        bool liftTooLow = liftPotValue < 825;
        bool liftTooHigh = liftPotValue > 3100;

        if(joystickGetDigital(1, 6, JOY_UP) && !liftTooHigh){
            dLift(false);
        }else if(joystickGetDigital(1, 6, JOY_DOWN) && !liftTooLow){
            dLift(true);
        }else if(joystickGetDigital(1, 8, JOY_UP)){
            setSyncLift(HIGH_HEIGHT);
        }else if(joystickGetDigital(1, 8, JOY_DOWN)){
            setSyncLift(MID_HEIGHT);
        }else{
            if(!runLift)
                stopLift();
        }

        if(joystickGetDigital(1, 5, JOY_DOWN)){
            closeClaw(OFF);
        }else if(joystickGetDigital(1, 5, JOY_UP)){
            openClaw();
        }else{
            mutexTake(clawClosingMutex, -1);
            clawClosing = false;
            mutexGive(clawClosingMutex);
        }

        if(joystickGetDigital(1, 7, JOY_UP)){
            gyroReset(gyroOne);
            gyroReset(gyroTwo);
            delay(500);
        }

        analogDrive();

        delay(20);
    }
}

```