```c
// Auton to run in square closest to flag
int autonTime=0;
void nearAuton(int side){
  clearTimer(T1);

  startTask(liftControl);
  liftPID.target = 850;
  motor[slingshot]=127;
  wait1Msec(2300);
  motor[slingshot]=0;


  pDrive(-1100);//Drive back to hit flag

  //turns claw towards ground

  pDrive(700);//drive back
  liftPID.target = 500;//put lift on ground for claw to grab cap
  startTask(clawTask);
  clawPID.target=800;
  pTurn(350 * side);//turn to face cap


  startTask(rotatorTask);
  rotatorPID.target = rotatorLowPos;


  pDrive(750);
  clawPID.target=50;//grap capa

  rotatorPID.target=rotatorHighPos;
  liftPID.target=850;//lift up
  wait1Msec(600);
  drive(127);
  wait1Msec(100);
  clawPID.target=800;
  wait1msec(100);
  drive(0);
  wait1Msec(100);

  pTurn(-350*side);//turn to face platform
  drive(127);
  wait1msec(2000);
  drive(-50);
  wait1Msec(50);
  drive(0);



  autonTime=time1[T1];

}
// Auton to run in sqaure farthest to flag
void farAuton(int side){
//red is 1, blue is -1
  clearTimer(T1);
  rotatorPID.target=rotatorLowPos;
  startTask(clawTask);
  startTask(liftControl)
```

```c
  clawPID.target=50;
  wait1Msec(500);

  liftPID.target=950;
  wait1Msec(500);

  startTask(rotatorTask);
  rotatorPID.target=rotatorLowPos;
  liftPID.target = 450;//put lift on ground for claw to grab cap
  drive(127);
  wait1Msec(1225);
  drive(0);
  pDrive(-200);
  clawPID.target=670;
  pTurn(-220*side);//turn to face second cap
  pDrive(520);


  clawPID.target=50;//grab second cap
  rotatorPID.target=rotatorHighPos//flip cap
  liftPID.target=1000;//lift up
  wait1Msec(600);
  liftPID.target=500;
  clawPID.target=800;//drop cap

  pTurn(520*side);//turn to face platform



  drive(127);
  wait1msec(1750);
  drive(-50);
  wait1Msec(50);
  drive(0);


  autonTime=time1[T1];
}
```