```c
//This file contains specific autonomous routiens

// Auton to run in square closest to flag
int autonTime=0;

void nearAutonFirstHalf(int side){
  motor[intake]=127;
  motor[slingshot]=127;
  pDrive(-450);
  clearTimer(T1);
  startTask(clawTask);
  clawPID.target=clawClosePos;
  startTask(liftControl);
  liftPID.target = 850;

  wait1Msec(2000);
  motor[slingshot]=0;


  pDrive(-670);//Drive back to hit flag

  //turns claw towards ground

  pDrive(600);//drive back
  liftPID.target = 500;//put lift on ground for claw to grab cap
  motor[intake]=0;


  pTurn(900 * side);//turn to face cap
  clawPID.target=clawOpenPos+30;


  startTask(rotatorTask);
  rotatorPID.target = rotatorLowPos;


  pDrive(700);
  clawPID.target=clawClosePos;//grap capa
  wait1Msec(200);
  rotatorPID.target=rotatorHighPos;
  liftPID.target=850;//lift up
  wait1Msec(600);
  drive(127);
  clawPID.target=clawOpenPos;
  wait1msec(200);
  drive(0);

  //pDrive(-0);//Drive back to align with platform
}

void nearAuton(int side){

  nearAutonFirstHalf(side);


  pTurn(-900*side);//turn to face platform
  clawPID.target=clawClosePos;
  drive(127);
  wait1msec(1850);
```

```c
  drive(-50);
  wait1Msec(50);
  drive(0);



  autonTime=time1[T1];

}

void prog(){
  nearAutonFirstHalf(BLUESIDE);
  pDrive(-500);
  pTurn(930);
  pDrive(1200);
  pTurn(-900);

  drive(127);
  wait1msec(2300);
  drive(-50);
  wait1Msec(50);
  drive(0);
}




// Auton to run in sqaure farthest to flag
void farAuton(int side){
//red is 1, blue is -1
  clearTimer(T1);
  clawIdle = false;
  rotatorPID.target=rotatorLowPos;
  startTask(clawTask);
  startTask(liftControl);
  getLiftOutOfTheWay();
  clawPID.target=clawClosePos;
  startTask(rotatorTask);
  rotatorPID.target=rotatorLowPos;
  //put lift on ground for claw to grab cap
  motor[intake] = 127;
  pDrive(-1300);//back up to hit cap
  pDrive(230);
  motor[intake] = 0;
  pTurn(900 * side);//turn to face second cap
  liftPID.target = 400;//put lift on ground for claw to grab cap
  clawPID.target=clawOpenPos+60;
  startTask(rotatorTask);
  rotatorPID.target = rotatorLowPos;
  pDrive(420);
  clawPID.target=clawClosePos;//grap capa
  wait1Msec(200);
  rotatorPID.target=rotatorHighPos;
  liftPID.target=850;
  wait1Msec(200);
  clawPID.target=clawOpenPos;
  pDrive(-200);
  pTurn(-900*side);
  pDrive(350);
```

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  pTurn(-900*side);//tur to face park

  clawPID.target=clawClosePos;
  drive(127);
  wait1msec(1250);
  drive(-127);
  wait1Msec(50);
  drive(0);


  //lift up
  /*
  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];
}
```