```c
/**
 * @file autoRight.c
 * @brief Right side autonomous routines
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 *
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 */

#include "../include/auto.h"

void autonRight12() {
	getMogo();                        // Get the mobile goal

	turnTo(5, 300);                  // Align to a right tilt
	driveSettings[0].max -= 40;       // Limit left side speed
	driveToPosition(300, 700, 2200); // Back up
	driveSettings[0].max += 40;       // Correct speed
	turnTo(165, 2000);               // Turn around
	delay(400);

	// Reset drive encoders & gyro
	sensorReset(drive[0].sensor);
	sensorReset(drive[1].sensor);
	sensorReset(&gyro);

	driveToPositionAngle(900, 1100, -13, 1850); // Drive arc -13 degrees
	GO(placeConeT, NULL);                       // Place cone
	mogoP(MOGO_DOWN);

	driveSet(-127, -127);                       // Back up the drive
	delay(130);
	mogoP(MOGO_DOWN - 300);                     // Bring the mobile goal up a bit
	delay(250);
	driveSet(0, 0);                             // Stop the drive
```

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        armSettings.target = arm.sensor->average;  // Reset the arm position to it's
                                                   // current position
} /* autonRight12 */

void autonRight22() {
        getMogo(); // Get the mobile goal

        gyroSettings[0].tolerance--;
        gyroSettings[1].tolerance--;
        turnTo(10, 575);                // Align to a right tilt
        gyroSettings[0].tolerance++;
        gyroSettings[1].tolerance++;
        driveSettings[0].max -= 40;      // Limit left side speed
        GO(placeConeT, NULL);            // Place cone
        driveToPosition(788, 388, 2200); // Back up
        driveSettings[0].max += 40;      // Correct speed
        turnTo(-158, 2000);              // Turn around

        // Reset drive encoders & gyro
        sensorReset(drive[0].sensor);
        sensorReset(drive[1].sensor);
        sensorReset(&gyro);

        driveToPositionAngle(1300, 1400, -13, 1800); // Drive arc -13 degrees

        // turnTo(59, 750);

        sensorReset(drive[0].sensor);
        sensorReset(drive[1].sensor);
        sensorReset(&gyro);

        driveToPositionAngle(1050, 1050, 0, 1425); // Drive straight

        driveSet(30, 30);
        mogoP(MOGO_DOWN);                          // Drop mobile goal

        // Wait a bit for the mobile goal to settle
        driveSet(100, 100);
        delay(350);

        driveSet(-127, -127); // Back up the drive
        delay(650);
        TaskHandle mogoUpHandle = GO(mogoPT, MOGO_UP);
        delay(500);           // Make sure that the robot isn't touching a field
                              // element
        driveSet(0, 0);       // stop the robot
```

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        while (taskGetState(mogoUpHandle) != TASK_DEAD) {
                delay(10);
        }

        armSettings.target = arm.sensor->average; // Reset the arm position to it's
                                                  // current position
} /* autonRight22 */
```