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/**
 * @file line.c
 * @brief line sensor stuff to make life easier
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 *
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 */

#include "../include/line.h"

typedef struct aful_t {
    int          *result;
    Mutex        mutex;
    unsigned long max;
} Aful;

Side getSide() {
    return line[0].value ? LEFT : RIGHT;
} /* getSide */

int getAngleFP(int p[4], Side s) {
    #ifdef DEBUG_MODE
        printf("\n\nr(%d, %d)\n(%d, %d)\n\n", p[0], p[1], p[2], p[3]);
    #endif
    return atan2(lineDistance, (double)(s ? p[3] - p[1] : p[2] - p[0]))
        * 180 / M_PI;
} /* getAngleFP */

void updateLinesDrive() {
    for (int i = 0; i < 3; i++) {
        sensorRefresh(&line[i]);
    }

    for (int i = 0; i < 2; i++) {
        sensorRefresh(drive[i].sensor);
    }
}

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    }
} /* updateLinesDrive */

Task angleFromUpcomingLineT(void *aful) {
    Aful *a = (Aful *)aful;

    while (!(line[0].value + line[2].value)) {
        updateLinesDrive();
        delay(20);
    }

    int p[4] = { drivePos(0), drivePos(1) };
    Side s = getSide();

    if (s == LEFT) {
        while (!line[2].value) {
            updateLinesDrive();
            delay(20);
        }
    } else {
        while (!line[0].value) {
            updateLinesDrive();
            delay(20);
        }
    }

    p[2] = drivePos(0);
    p[3] = drivePos(1);

    *(a->result) = (millis() <= a->max) ? getAngleFP(p, s) : 0;
    mutexGive(a->mutex);
    free(aful);
    taskDelete(NULL);
} /* angleFromUpcomingLineT */

Mutex angleFromUpcomingLine(int *store, Mutex m, unsigned long maxTime) {
    Aful *a = new(Aful);

    a->result = store;
    a->mutex = m ? m : mutexCreate();
    a->max = millis() + maxTime;
    mutexTake(a->mutex, -1);
    GO(angleFromUpcomingLineT, a);
    return a->mutex;
} /* angleFromUpcomingLine */

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