```c
/**
 * @file autoSkills.c
 * @brief Programming skills
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 *
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 */

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

void autonLeft22();
void liftPID(void *none);

void autonSkills() {
	// Get the mobile goal using the left red 22 point auton routine
	autonLeft22();

	// ////////////////////////////////////////////////////////////////// 22 POINTS

	resetDrive();

	driveToPosition(-200, -200, 750);
	turnTo(136, 2500);     // TURN AROUND,
	GO(mogoPT, MOGO_DOWN); // DROP A MOGO INTAKE;
	delay(350);

	// Reset sensors
	resetDrive();
	driveToPositionAngle(685, 675, 135, 1550);
	sensorRefresh(sonic);
	#ifdef DEBUG_MODE
		printf("\n\n%d\n\n", sonic->value);
	#endif
	turnTo(203, 2500); // TURN AROUND,
```

```
// Reset sensors
resetDrive();

driveToPositionAngle(1650, 1650, 206, 3200);

// Mogo intake up
mogoP(MOGO_UP + 100);
turnTo(380, 2900); // TUUUURN AROUUUND

// Reset sensors
resetDrive();

driveToPositionAngle(1300, 1400, 373, 1875);
// Bring mogo intake to middle
TaskHandle mogoHandle = GO(mogoPT, MOGO_MID);
driveToPositionAngle(2375, 2475, 371, 2750);

if (taskGetState(mogoHandle))
        taskDelete(mogoHandle);
mogoP(MOGO_DOWN);
driveSet(-64, -64);
delay(150);

GO(mogoPT, MOGO_MID - 100);
delay(150);

driveSet(70, 70);
delay(200);
driveSet(28, 28);
delay(300);
driveSet(10, 10);
delay(125);
sensorReset(&gyro);

static const float driveChange = .76;
driveSettings[0].kP *= driveChange;
driveSettings[1].kP *= driveChange;
driveToPosition(2325, 2325, 1800);
driveSettings[0].kP /= driveChange;
driveSettings[1].kP /= driveChange;


// ////////////////////////////////////////////////////////////////// 32 POINTS

turnTo(-104, 3400);
```

```
sensorRefresh(sonic);
#ifdef DEBUG_MODE
        printf("\n\n%d\n\n", sonic->value);
#endif

driveSet(44, 44);
int sonicGoal = 43; // 62;

do {
        sensorRefresh(sonic);
        info();
        delay(20);
} while (sonic->value == 0 || sonic->value > sonicGoal);
driveSet(-35, -35);
delay(175);
driveSet(0, 0);

turnTo(-201, 2900); // TURN AROUND,

// Reset sensors
resetDrive();

mogoHandle = GO(mogoPT, MOGO_DOWN);
delay(300);
driveToPositionAngle(1430, 1430, -205, 2600);

// Mogo intake up
mogoP(MOGO_UP);
driveToPositionAngle(750, 750, -204, 1200);
turnTo(-362, 2000); // TUUUURN AROUUUND

// Reset sensors
resetDrive();

driveToPositionAngle(900,  800,  -354, 1876);
// Bring mogo intake to middle
mogoHandle = GO(mogoPT, MOGO_MID);
driveToPositionAngle(1325, 1225, -343, 2200);
driveSet(17, 17);
delay(250);

if (taskGetState(mogoHandle))
        taskDelete(mogoHandle); mogoP(MOGO_DOWN);
driveSet(10, 10);
delay(250);
```

```
// Reset drive and gyro sensors
resetDrive();
sensorReset(&gyro);

driveSet(-64, -64);
delay(250);
mogoHandle = GO(mogoPT, MOGO_MID);
// Back up a small amount
driveToPosition(-450, -450, 750);

// ////////////////////////////////////////////////////////////////// 42 POINTS

// Turn around to aim for the red mogo across the field
turnTo(175, 3000);
resetDrive();

// Drive across the field
driveToPositionAngle(600,  600,  176, 1200);
// Mogo intake down to pick it up
mogoHandle = GO(mogoPT, MOGO_DOWN);
driveToPositionAngle(3300, 3200, 174, 3900);
mogoHandle = GO(mogoPT, MOGO_MID - 200);
driveToPosition(3700, 3600, 1200);
turnTo(173, 600);

resetDrive();

driveToPosition(100,  500,  1000);
driveToPosition(830,  1180, 800);
driveToPosition(1380, 1280, 1000);
driveToPositionAngle(1600, 1500, 185, 1700);

mogoHandle = GO(mogoPT, MOGO_MID + 125);
driveSet(127, 127);
delay(450);

// Reset drive encoders & gyro
// resetDrive();

if (taskGetState(mogoHandle))
        taskDelete(mogoHandle);
mogo.power = 127;
motorUpdate(&mogo);
driveSet(64, 64);

delay(175);
```

```
sensorReset(&gyro);

mogo.power = 30;
motorUpdate(&mogo);
driveSet(-127, -127);

delay(125);

if (taskGetState(mogoHandle))
        taskDelete(mogoHandle); mogoHandle = GO(mogoPT, MOGO_MID);

driveToPosition(1100, 1000, 2095);

driveSet(70, 70);
delay(250);
driveSet(28, 28);
delay(300);
driveSet(10, 10);
delay(150);
sensorReset(&gyro);
resetDrive();

// ////////////////////////////////////////////////////////////////// 62 POINTS

// driveSettings[0].kP *= driveChange;
// driveSettings[1].kP *= driveChange;
driveToPosition(-100, -100, 750);
// driveSettings[0].kP /= driveChange;
// driveSettings[1].kP /= driveChange;

turnTo(-102, 3400);

sensorRefresh(sonic);
#ifdef DEBUG_MODE
        printf("\n\n%d\n\n", sonic->value);
#endif

driveSet(44, 44);
sonicGoal = 84;

do {
        sensorRefresh(sonic);
        info();
        delay(20);
} while (sonic->value == 0 || sonic->value > sonicGoal);
driveSet(-35, -35);
```

```
        delay(175);
        driveSet(0, 0);

        turnTo(-216, 2900); // TURN AROUND,

        // Reset sensors
        resetDrive();

        mogoHandle = GO(mogoPT, MOGO_DOWN);
        delay(300);
        driveToPositionAngle(1430, 1430, -220, 2600);

        // Mogo intake up
        mogoP(MOGO_UP);
        driveToPositionAngle(750, 750, -219, 1200);
        turnTo(-355, 2000); // TUUUURN AROUUUND

        // Reset sensors
        resetDrive();

        driveToPositionAngle(900,  800,  -347, 1876);
        // Bring mogo intake to middle
        mogoHandle = GO(mogoPT, MOGO_MID);
        driveToPositionAngle(1325, 1225, -336, 2200);

        // Reset sensors
        resetDrive();

        if (taskGetState(mogoHandle))
                taskDelete(mogoHandle); mogoP(MOGO_DOWN);
        driveSet(17, 17);
        delay(250);

        resetDrive();
        sensorReset(&gyro);

        driveSet(-64, -64);
        delay(250);
        mogoHandle = GO(mogoPT, MOGO_MID);
        // Back up a small amount
        driveToPosition(-450, -450, 750);

        // ////////////////////////////////////////////////////////////////// 72 POINTS
} /* autonSkills */
```