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/**
 * @file line.h
 * @brief Utilities for the three line sensors
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 *
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 */

#ifndef CARL_LINE_H_
#define CARL_LINE_H_

#include "robot.h"

#define gline(index) (line[index].value)

/*
 * The distance between line sensors, the first number is inches and everything
 * else converts -> ticks
 */
static const double lineDistance = 80.25791219881197;

typedef enum {
    LEFT = 0,
    RIGHT = 1,
} Side;

/**
 * @brief Get the current Side. Really simple.
 *
 * @return the current Side, LEFT or RIGHT
 */
Side    getSide();

/**
 * @brief Take and delete a mutex. If it can't be taken, don't delete it.

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*
* @param m the Mutex to take (then delete)
* @param blockTime the maximim time to wait before giving up
*
* @return Whether or not the mutex was taken
*/
inline bool mutexTakeDelete(Mutex m, unsigned long blockTime) {
    if (!mutexTake(m, blockTime)) {
        return false;
    }

    mutexDelete(m);
    return true;
} // mutexTakeDelete

/**
* @brief Calculate the angle of the robot based on the positions of the left
* and right drive from when each line sensor hit the line
*
* @param p an array of the 4 positions, in the order: L1, R1, L2, R2
* @param o which line sensor hit the line first
*
* @return the angle, in degrees clockwise, of the robot relative to the line.
* If something goes wrong, it will result 0 (I think. Don't quote me on that)
*/
int getAngleFP(int p[4], Side o);

/**
* @brief Get the angle from the upcoming line when it is hit and store it
*
* @param store a pointer to where the angle is to be stored
* @param m the Mutex to use, if one already exists. If not, use NULL
* @param maxTime the maximum amount of time the get can take
*
* @return A Mutex that will be released when the angle is stored
*/
Mutex angleFromUpcomingLine(int *store,
                             Mutex mutex,
                             unsigned long maxTime);

#endif // ifndef CARL_LINE_H_

```