

```

/**
 * @file autoStack.c
 * @brief Drive forward and stack cones from the loader
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 *
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 */

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

void updateLinesDrive();

void autonStack() {
    update();
    driveSet(35, 35);
    int angle;

    Mutex m = angleFromUpcomingLine(&angle, NULL, 5000);
    mutexTakeDelete(m, -1);

    angle = -angle;

#ifdef DEBUG_MODE
    printf("\n\n\r%d\n\n", angle);
#endif
    sensorRefresh(&gyro);
#ifdef DEBUG_MODE
    printf("\n\n\r%d\n\n", gyro.average);
#endif
    gyro.zero = angle;
    gyro.child->zero = angle;
    sensorRefresh(&gyro);
#ifdef DEBUG_MODE
    printf("\n\n\r%d\n\n", gyro.average);
#endif
}

```

```

driveToPositionAngle(drivePos(0) - 300, drivePos(1) - 300, 0, 2000);

turnTo(90, 3500);

#ifdef DEBUG_MODE
    print("\n\nreturned and stuff\n\n");
#endif

driveSet(25, 25);
while (gline(0) + gline(1) + gline(2)) {
    updateLinesDrive();
    delay(10);
}

claw.power = 50;
motorUpdate(&claw);
armSettings.target = ARM_3_QUARTER;
TaskHandle delet = GO(armPID, NULL);

driveToPositionAngle(drivePos(0) + 350, drivePos(1) + 350, 90, 1600);

taskDelete(delet);
armToPosition(ARM_3_QUARTER, 750);

#ifdef DEBUG_MODE
    print("\n\nrready to stack\n\n");
#endif

for (int i = 0; i < 5; i++) {
    claw.power = -75;
    update();
    delay(500);
    claw.power = -30;
    update();
    armToPosition(ARM_QUARTER / 2 + (ARM_QUARTER * .25 * i), 3000);
    claw.power = 127;
    update();
    delay(400);
    claw.power = 10;
    update();
    armToPosition(ARM_3_QUARTER, 3000);
}
} /* autonLeftRed12 */

```