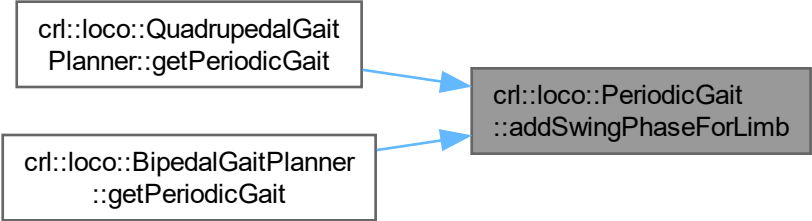


crl::loco::QuadrupedalGait
Planner::getPeriodicGait

crl::loco::BipedalGaitPlanner
::getPeriodicGait

crl::loco::PeriodicGait
::addSwingPhaseForLimb



```
graph LR; A[crl::loco::QuadrupedalGaitPlanner::getPeriodicGait] --> C[crl::loco::PeriodicGait::addSwingPhaseForLimb]; B[crl::loco::BipedalGaitPlanner::getPeriodicGait] --> C;
```

The diagram illustrates a callout mechanism. Two white boxes on the left, each with a black border, contain the text 'crl::loco::QuadrupedalGaitPlanner::getPeriodicGait' and 'crl::loco::BipedalGaitPlanner::getPeriodicGait' respectively. Two blue arrows originate from the right side of these boxes and point towards a central gray box on the right. The gray box contains the text 'crl::loco::PeriodicGait::addSwingPhaseForLimb'.