

findClosestPointToRobot



```
graph LR; A[findClosestPointToRobot] --> B["ca.mcgill.ecse211.odometer.Odometer.getOdometer"]; A --> C["ca.mcgill.ecse211.odometer.OdometerData.getXYT"]; A --> D[distanceFrom];
```

The diagram illustrates the dependencies of the `findClosestPointToRobot` function. It is represented by a grey rectangular box on the left. Three blue arrows originate from the right side of this box and point to three separate white rectangular boxes on the right. The top arrow points to a box containing the code `ca.mcgill.ecse211.odometer.Odometer.getOdometer`. The middle arrow points to a box containing the code `ca.mcgill.ecse211.odometer.OdometerData.getXYT`. The bottom arrow points to a box containing the code `distanceFrom`.

ca.mcgill.ecse211.odometer.  
Odometer.getOdometer

ca.mcgill.ecse211.odometer.  
OdometerData.getXYT

distanceFrom