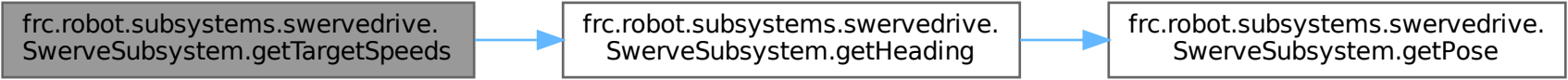


```
frc.robot.subsystems.swervedrive.  
SwerveSubsystem.getTargetSpeeds
```



```
graph LR; A[frc.robot.subsystems.swervedrive.  
SwerveSubsystem.getTargetSpeeds] --> B[frc.robot.subsystems.swervedrive.  
SwerveSubsystem.getHeading]; B --> C[frc.robot.subsystems.swervedrive.  
SwerveSubsystem.getPose];
```

```
frc.robot.subsystems.swervedrive.  
SwerveSubsystem.getHeading
```

```
frc.robot.subsystems.swervedrive.  
SwerveSubsystem.getPose
```