

frc.robot.subsystems.swervedrive.
SwerveSubsystem.getVisionPose

frc.robot.subsystems.swervedrive.
SwerveSubsystem.setupPhotonVision

frc.robot.subsystems.swervedrive.
SwerveSubsystem.updatePoseWithVision

frc.robot.subsystems.swervedrive.
Vision.updatePoseEstimation

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graph LR; A[frc.robot.subsystems.swervedrive.SwerveSubsystem.getVisionPose] --> D[frc.robot.subsystems.swervedrive.Vision.updatePoseEstimation]; B[frc.robot.subsystems.swervedrive.SwerveSubsystem.setupPhotonVision] --> D; C[frc.robot.subsystems.swervedrive.SwerveSubsystem.updatePoseWithVision] --> D;
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The diagram illustrates a dependency or data flow. On the left, three white rectangular boxes with black borders contain the following text: 'frc.robot.subsystems.swervedrive.SwerveSubsystem.getVisionPose', 'frc.robot.subsystems.swervedrive.SwerveSubsystem.setupPhotonVision', and 'frc.robot.subsystems.swervedrive.SwerveSubsystem.updatePoseWithVision'. On the right, a single gray rectangular box with a black border contains the text 'frc.robot.subsystems.swervedrive.Vision.updatePoseEstimation'. Three blue arrows originate from the right side of each white box and point towards the left side of the gray box, indicating that the three SwerveSubsystem methods are used or called by the Vision.updatePoseEstimation method.