

frc.robot.subsystems.swervedrive.
SwerveSubsystem.aimAtSpeaker

frc.robot.subsystems.swervedrive.
SwerveSubsystem.getTargetSpeeds

frc.robot.subsystems.swervedrive.
SwerveSubsystem.getTargetSpeeds

frc.robot.subsystems.swervedrive.
SwerveSubsystem.getHeading

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

The diagram illustrates a code refactoring or consolidation. On the left, there are three separate boxes, each containing a method call from the `frc.robot.subsystems.swervedrive.SwerveSubsystem` class. The top box contains `aimAtSpeaker`, the middle box contains `getTargetSpeeds`, and the bottom box contains `getTargetSpeeds`. Three blue arrows originate from the right side of these three boxes and point towards a single box on the right. This box, which has a gray background, contains the method call `getHeading`. This visualizes the consolidation of three separate calls into a single one.