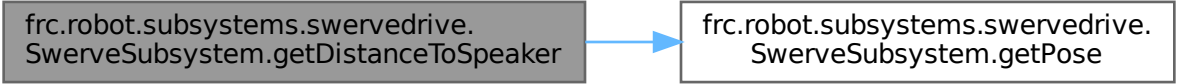


```
frc.robot.subsystems.swervedrive.  
SwerveSubsystem.getDistanceToSpeaker
```



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

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