

kinematics::camera  
::image2pos

ros\_func::ImageSurfaceMarker

kinematics::pose::projection

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graph LR; A[kinematics::camera::image2pos] --> C[kinematics::pose::projection]; B[ros_func::ImageSurfaceMarker] --> C;
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The diagram illustrates a data flow or dependency. On the left, there are two rectangular boxes. The top box contains the text 'kinematics::camera::image2pos'. The bottom box contains the text 'ros\_func::ImageSurfaceMarker'. On the right, there is a single rectangular box with a light gray fill, containing the text 'kinematics::pose::projection'. Two blue arrows originate from the right side of the left boxes and point towards the left side of the right box, indicating that both 'kinematics::camera::image2pos' and 'ros\_func::ImageSurfaceMarker' are inputs or dependencies for 'kinematics::pose::projection'.