

PickPlace

- + pickPose : geometry_msgs/Pose
- + placePose : geometry_msgs/Pose
- + homePose : geometry_msgs/Pose
- + setArmPose : ros::ServiceClient
- + setGripperState : ros::ServiceClient
- + robotState : bool
- + pnpNode : ros::NodeHandle

- + executePick(ros::Nodehandle) : bool
- + executePlace(ros::NodeHandle) : bool
- + setPose(geometry_msgs::Pose) : bool
- + setGripper(vector<double>) : bool