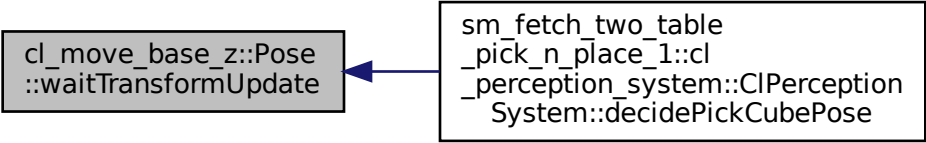


```
cl_move_base_z::Pose  
::waitTransformUpdate
```



```
graph LR; A["sm_fetch_two_table  
_pick_n_place_1::cl  
_perception_system::ClPerception  
System::decidePickCubePose"] --> B["cl_move_base_z::Pose  
::waitTransformUpdate"]
```

A diagram showing a call from a perception system to a move_base pose waiter. On the right, a box contains the code for a state machine function that fetches a table, picks a place, and uses a perception system to decide a pick cube pose. A blue arrow points from this box to a box on the left, which contains the code for a pose waiter that waits for a transform update.

```
sm_fetch_two_table  
_pick_n_place_1::cl  
_perception_system::ClPerception  
System::decidePickCubePose
```