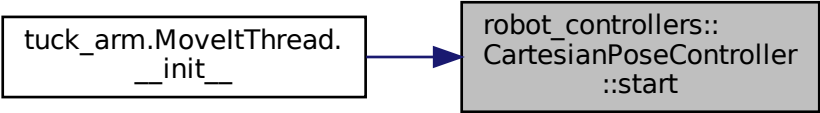


```
tuck_arm.MoveItThread.  
  __init__
```



```
graph LR; A[tuck_arm.MoveItThread.__init__] --> B[robot_controllers::CartesianPoseController::start];
```

A diagram showing a call from the `tuck_arm.MoveItThread.__init__` function to the `robot_controllers::CartesianPoseController::start` function. The first box is white with a black border, and the second box is gray with a black border. A blue arrow points from the first box to the second box.

```
robot_controllers::  
CartesianPoseController  
  ::start
```