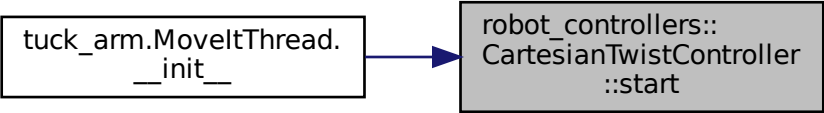


```
tuck_arm.MoveItThread.  
  __init__
```



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

A diagram showing a call from `tuck_arm.MoveItThread.__init__` to `robot_controllers::CartesianTwistController::start`. 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::  
CartesianTwistController  
  ::start
```