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graph RL; S1[sm_moveit_screw_loop  
::place_states::StNavigation  
Posture::runtimeConfigure] --> S2[sm_moveit_screw_loop  
::place_states::StNavigation  
Posture::onSuccessfulExit]; S2 --> S3[sm_moveit_screw_loop  
::cl_perception_system  
::ClPerceptionSystem::nextCube];
```

sm\_moveit\_screw\_loop  
::cl\_perception\_system  
::ClPerceptionSystem::nextCube

sm\_moveit\_screw\_loop  
::place\_states::StNavigation  
Posture::onSuccessfulExit

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