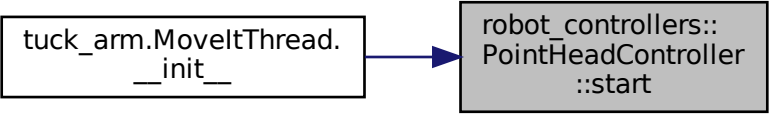


```
tuck_arm.MoveItThread.  
  __init__
```



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

```
robot_controllers::  
PointHeadController  
  ::start
```