

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



```
graph LR; A["sm_moveit::cl_perception  
_system::ClPerceptionSystem  
::decidePickCubePose"] --> B["cl_move_base_z::Pose  
::waitTransformUpdate"]
```

A diagram showing a call from a perception system to a move base system. On the right, a white box contains the text "sm_moveit::cl_perception _system::ClPerceptionSystem ::decidePickCubePose". A blue arrow points from this box to a gray box on the left, which contains the text "cl_move_base_z::Pose ::waitTransformUpdate".

```
sm_moveit::cl_perception  
_system::ClPerceptionSystem  
::decidePickCubePose
```