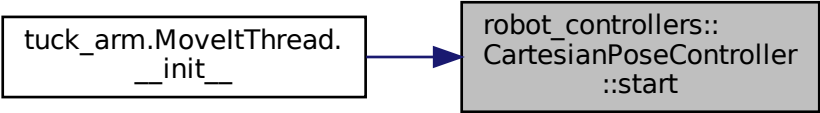


```
tuck_arm.MoveItThread.  
  __init__
```



```
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 source function is in a white box on the left, and the target function is in a gray box on the right, connected by a blue arrow.

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