

sm\_moveit\_2::cl\_perception  
\_system::CIPerceptionSystem  
::decidePickCubePose

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graph LR; A["sm_moveit_2::cl_perception_system::decidePickCubePose"] --> B["cl_move_base_z::Pose::toPoseStampedMsg"]; A --> C["cl_move_base_z::Pose::waitTransformUpdate"]
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cl\_move\_base\_z::Pose  
::toPoseStampedMsg

cl\_move\_base\_z::Pose  
::waitTransformUpdate