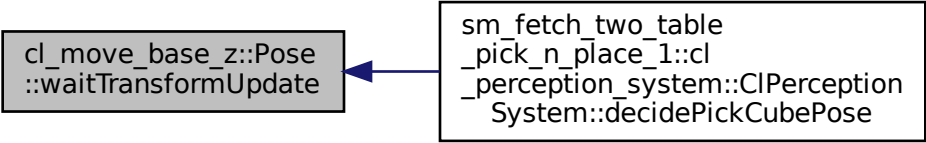


```
cl_move_base_z::Pose  
::waitTransformUpdate
```



```
graph LR; A["sm_fetch_two_table  
_pick_n_place_1::cl  
_perception_system::ClPerception  
System::decidePickCubePose"] --> B["cl_move_base_z::Pose  
::waitTransformUpdate"]
```

A diagram showing a call from a perception system to a move_base pose waiter. On the right, a box contains the code: `sm_fetch_two_table`, `_pick_n_place_1::cl`, and `_perception_system::ClPerception System::decidePickCubePose`. A blue arrow points from this box to a gray box on the left, which contains the code: `cl_move_base_z::Pose` and `::waitTransformUpdate`.

```
sm_fetch_two_table  
_pick_n_place_1::cl  
_perception_system::ClPerception  
System::decidePickCubePose
```