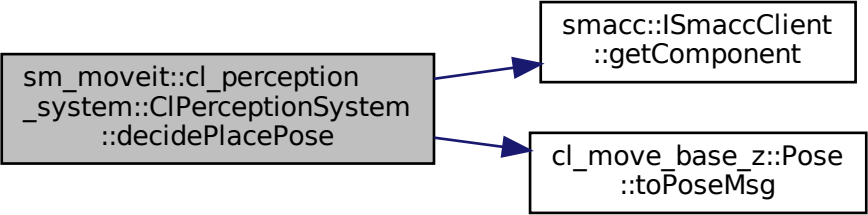


sm_moveit::cl_perception
_system::ClPerceptionSystem
::decidePlacePose



```
graph LR; A["sm_moveit::cl_perception_system::ClPerceptionSystem::decidePlacePose"] --> B["smacc::ISmaccClient::GetComponent"]; A --> C["cl_move_base_z::Pose::toPoseMsg"]
```

smacc::ISmaccClient
::GetComponent

cl_move_base_z::Pose
::toPoseMsg