

sm\_moveit\_2::cl\_perception  
\_system::ClPerceptionSystem  
::decidePlacePose

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graph LR; A["sm_moveit_2::cl_perception_system::ClPerceptionSystem::decidePlacePose"] --> B["smacc::ISmaccClient::GetComponent"]; A --> C["cl_move_base_z::Pose::toPoseMsg"]
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smacc::ISmaccClient  
::GetComponent

cl\_move\_base\_z::Pose  
::toPoseMsg