

sm_moveit_4::cl_perception
_system::ClPerceptionSystem
::decidePlacePose

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graph LR; A["sm_moveit_4::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