

sm_moveit::cl_perception
_system::ClPerceptionSystem
::decidePickCubePose

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graph LR; A["sm_moveit::cl_perception_system::ClPerceptionSystem::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