

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