

sm_moveit_4::cl_perception
_system::CIPerceptionSystem
::decidePickCubePose

```
graph LR; A["sm_moveit_4::cl_perception_system::decidePickCubePose"] --> B["cl_move_base_z::Pose::toPoseStampedMsg"]; A --> C["cl_move_base_z::Pose::waitTransformUpdate"]
```

cl_move_base_z::Pose
::toPoseStampedMsg

cl_move_base_z::Pose
::waitTransformUpdate