

sm\_aws\_warehouse\_navigation  
::StAcquireSensors::sendInitial  
PoseEstimation



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graph LR; A[sm_aws_warehouse_navigation::StAcquireSensors::sendInitialPoseEstimation] --> B[cl_nav2z::Amcl::setInitialPose]
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cl\_nav2z::Amcl::setInitialPose