Checking the arranged Points

Preparation

In order to send the robot to the point, the robot must be:

- **in automatic mode**

  In order to determine in what mode, the robot is, you need to see what the last message in the topic **/drive/mode** was.

  To read the message you need to run the command:

  rostopic echo/drive/mode

  0 - controller mode;

  1 - automatic mode.

  Attention! When you go to the service menu or in the robot settings, the robot automatically switches to controller mode, when exiting these menus, the robot will return to the previous mode. If the mode was switched in one of these menus, it will only be applied when exiting the service menu (or robot settings).

- **the robot is not paused**

  In order to determine in what state, the robot is, you need to see what the last message in the topic **/drive/pause** was.

  To read the message you need to run the command:

  rostopic echo/drive/pause

  false - the robot is not paused;

  true - the robot is paused.

Sending to the point

To send a robot to a point, you need to run the command:

rostopic pub/drive/point std_msgs/UInt16 "data: id" -1

where id is the number of the point at which the robot must arrive.

After arriving at the point, the travel module will automatically switch to the **pause** algorithm (waiting for new commands from the topic **/drive/mode**)

> **Attention!** When the module of movement in algorithm is paused, the robot will accept commands on movement only from a topic **/drive/mode**. This means that when sending the desired position via **Rviz**, the travel module ignores this command.

In order to avoid this situation, you need to switch the travel module to the **to_point_map** algorithm each time before sending the robot to the point via **Rviz**. To switch the travel module into the **to_point_map** algorithm, you need to execute the command:
rosservice call/drive/algo "name: 'to_point_map'"