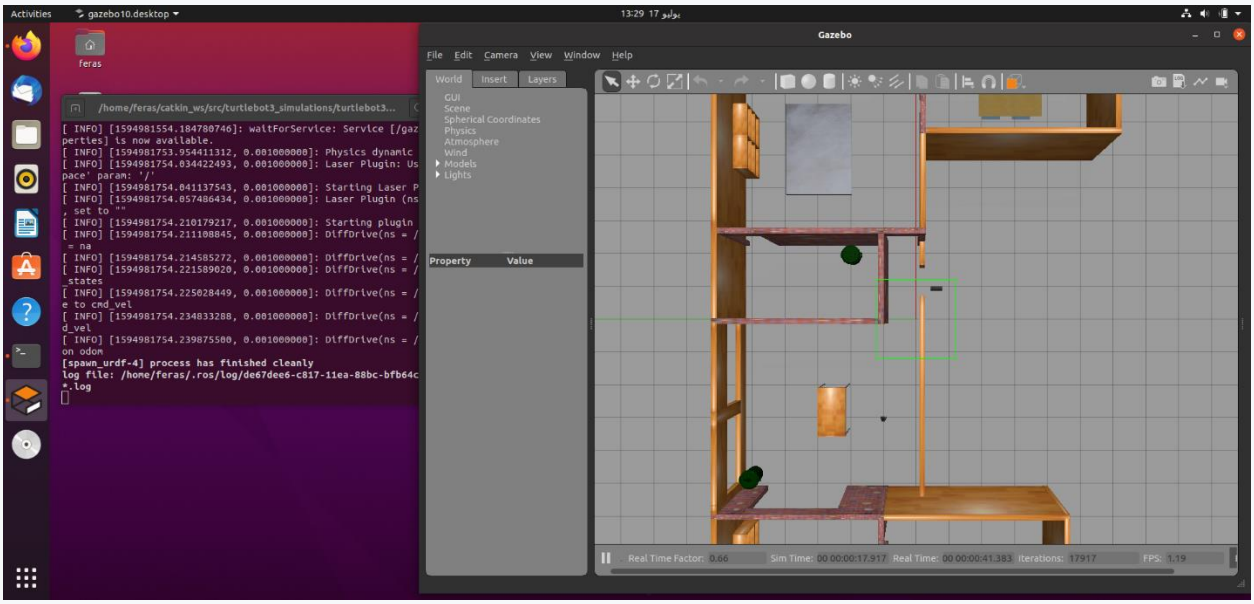
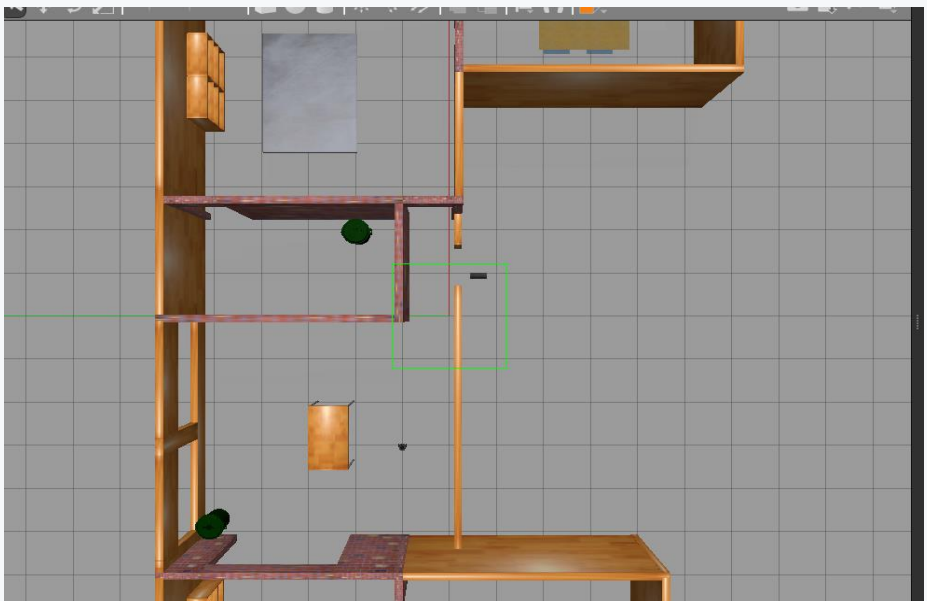
TurtleBot3 SLAM task

In the beginning, we are gonna run Gazebo World in order to see the map

The used world is Turtlebot3 House and the used turtlebot model is burger.

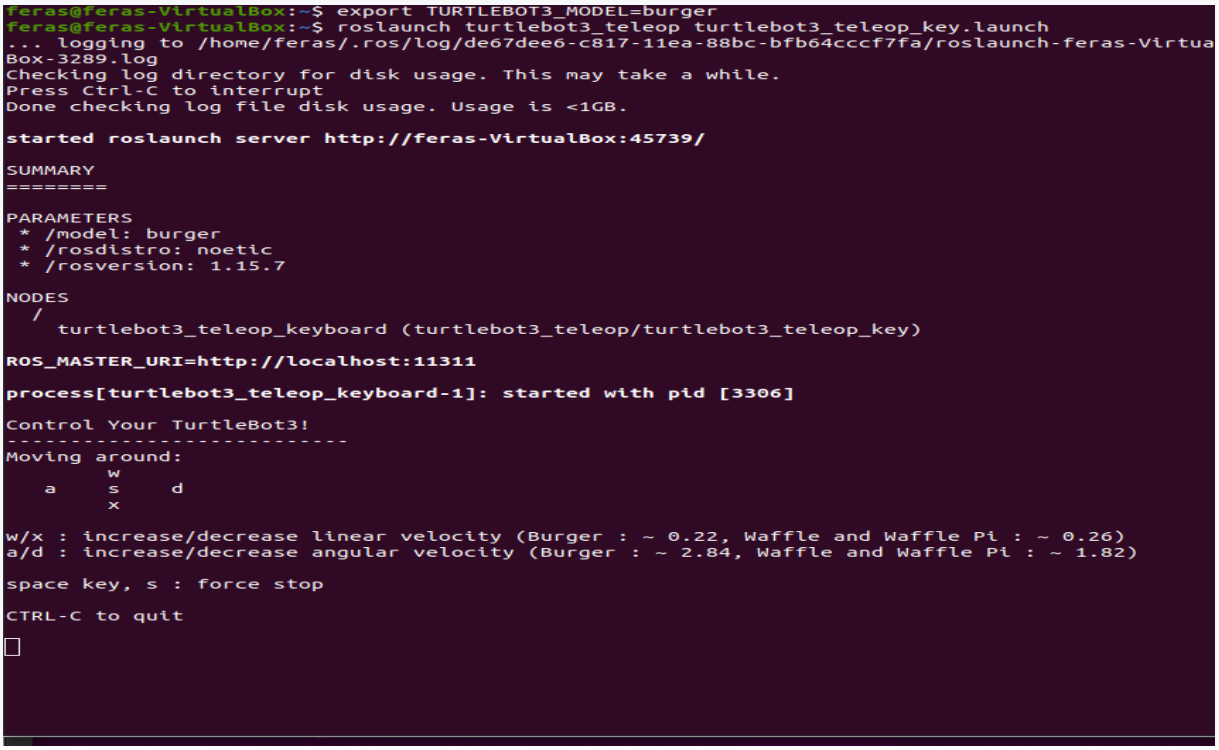
```
export TURTLEBOT3_MODEL=burger

roslaunch turtlebot3_gazebo turtlebot3_house.launch
```





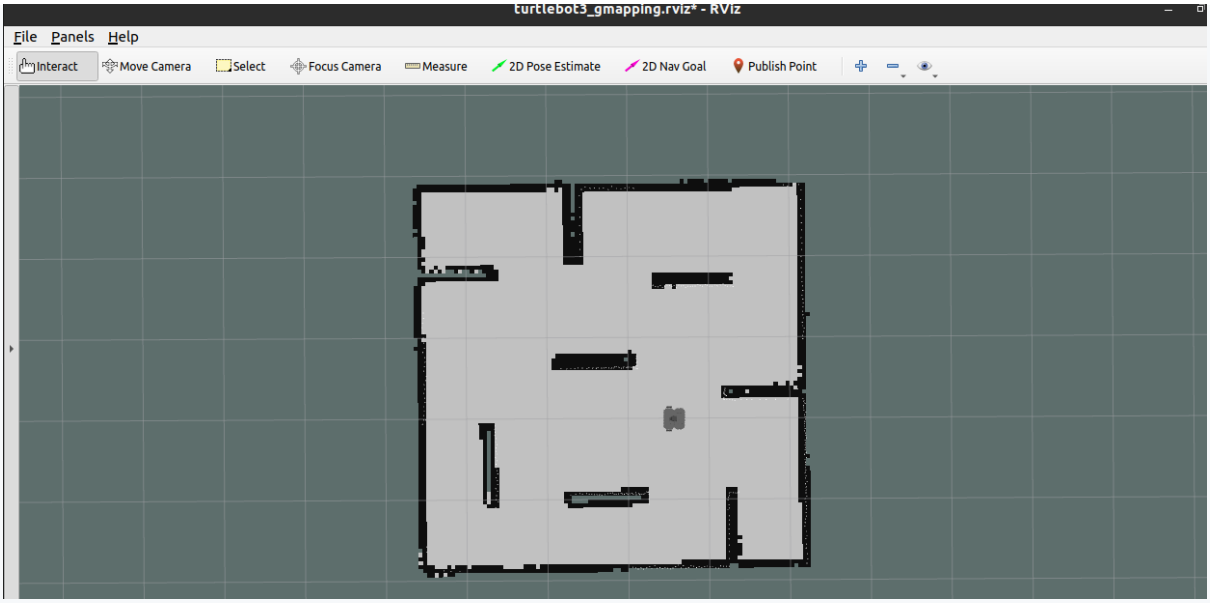
In order to control a TurtleBot3 with a keyboard. Open new terminal.

```
export TURTLEBOT3_MODEL=burger

roslaunch turtlebot3_teleop turtlebot3_teleop_key.launch
```



Thirdly, open new terminal and export the robot model and run the SLAM node in RViz.

```
export TURTLEBOT3_MODEL=burger

roslaunch turtlebot3_slam turtlebot3_slam.launch slam_methods:=gmapping
```



Note: we got error in the last part we fixed it by:

Open work space

git clone https://github.com/ros-perception/openslam_gmapping src/openslam_gmapping

git clone https://github.com/ros-perception/slam_gmapping src/slam_gmapping

rosdep install --from-paths src/ -i

catkin_make
-DCMAKE_BUILD_TYPE=RelWithDebInfo