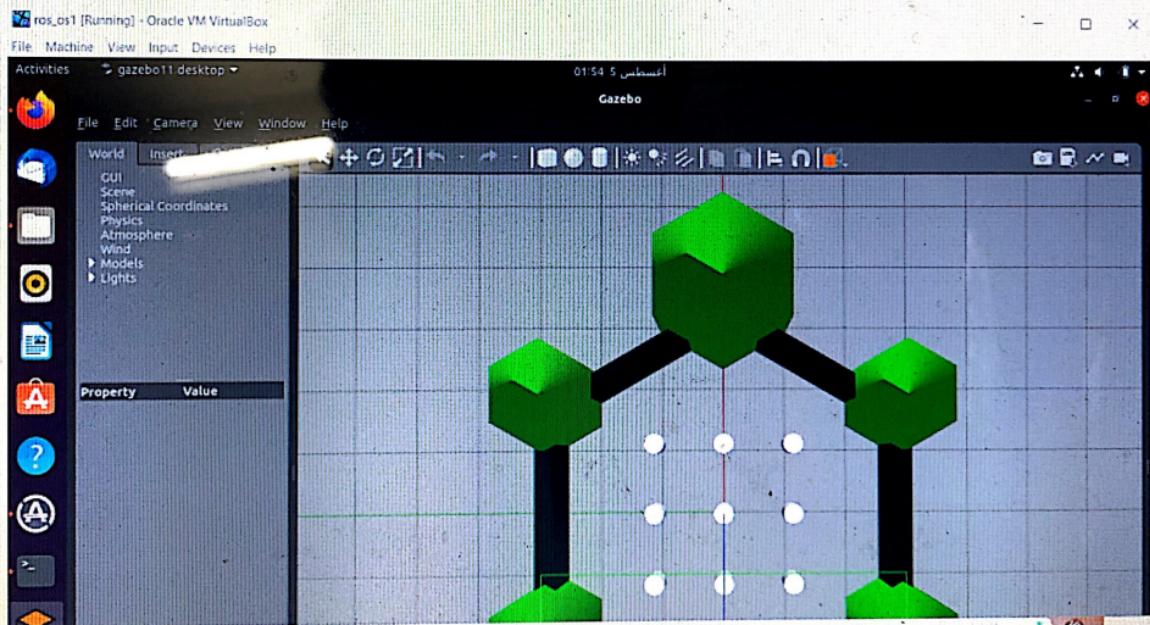


```
roslaunch turtlebot3_gazebo turtlebot3_world.launch
```

# The world would launch



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

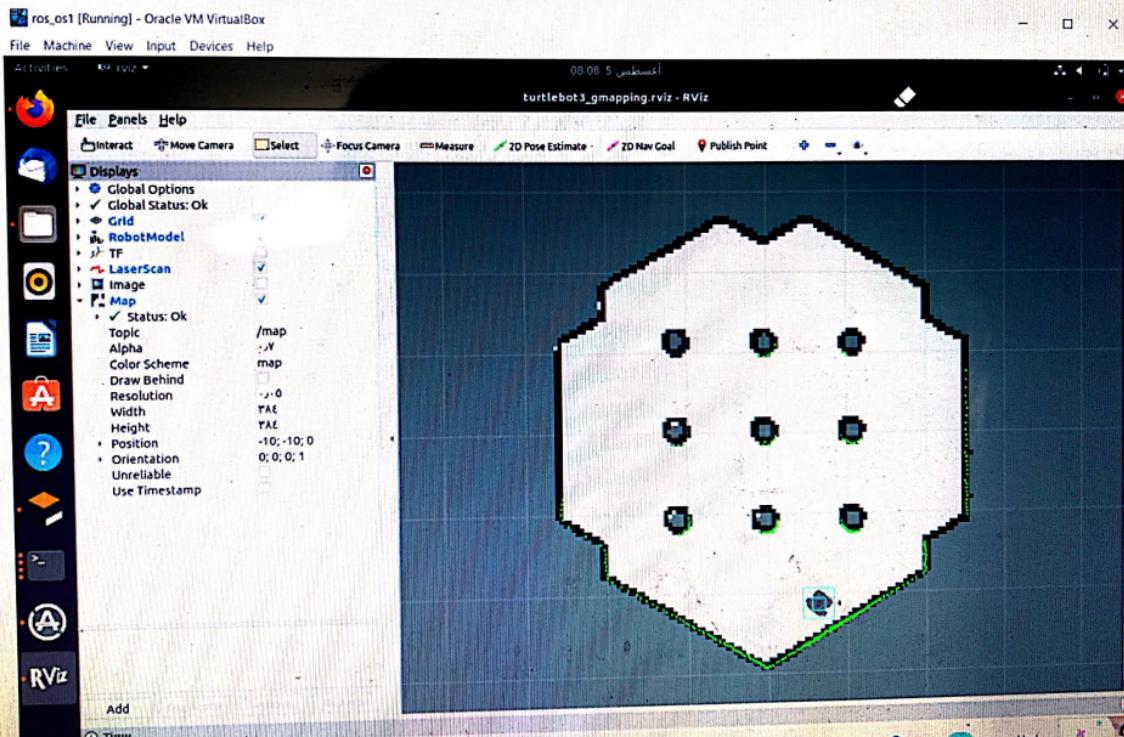
## To run the SLAM

```
$ rosrun turtlebot3 teleop turtlebot3 teleop key.launch
```

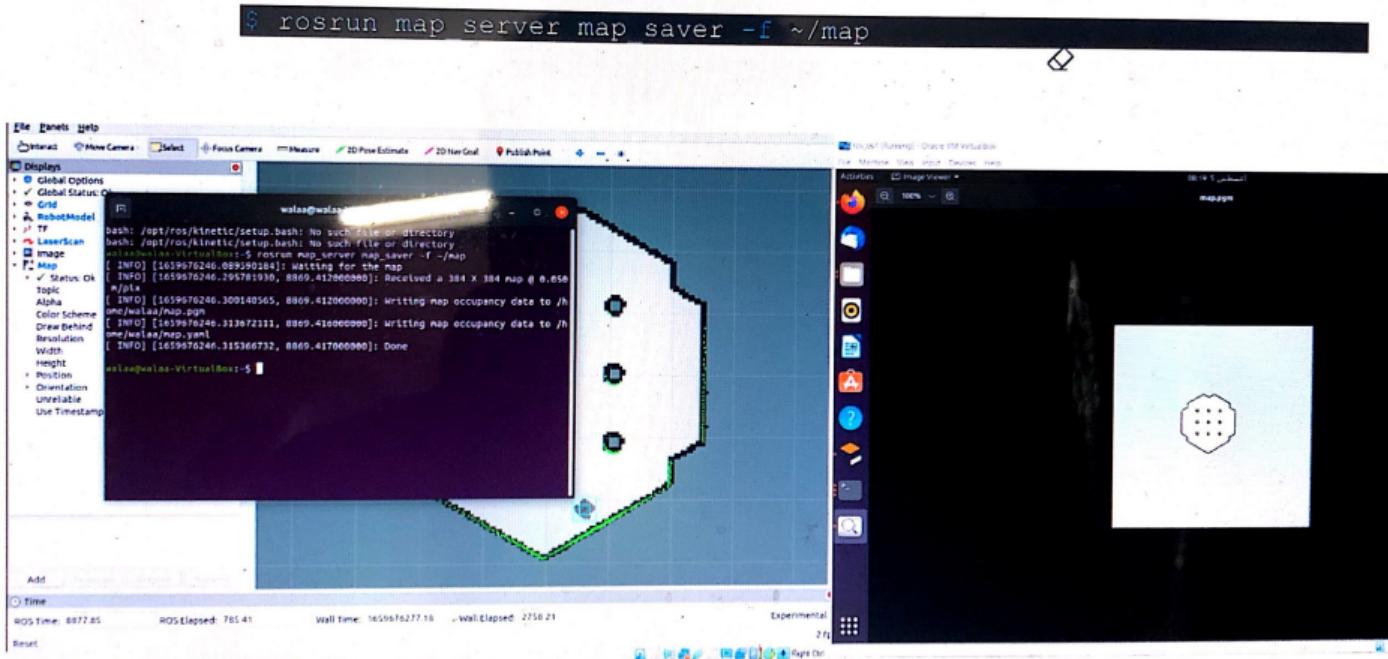
```
/  
  turtlebot3_teleop_keyboard (turtlebot3_teleop/turtlebot3_teleop_key)  
ROS_MASTER_URI=http://localhost:11311  
process[turtlebot3_teleop_keyboard-1]: started with pid [55741]  
  
control Your TurtleBot3!  
-----  
Moving around:  
    w  
    a    s    d  
    x  
  
    -/x : increase/decrease linear velocity (Burger : ~ 0.22, Waffle and Waffle Pi :  
    ~ 0.26)  
    -/d : increase/decrease angular velocity (Burger : ~ 2.84, Waffle and Waffle Pi  
    ~ 1.82)  
  
    space key, s : force stop  
  
    CTRL-C to quit
```

after moving the car the map will be created.

# after moving the car the map will be created.



# Finally Saving the map.



Scanned with CamScanner