**sanity** - will print the critical environment variables so you can verify you have configured things correctly.

* **set-turtlebot T10**- this function will automatically set the desired environment variables for you for each of the robots
* **unset-turtlebot** - this function unset and set all environment variables to their defaults. Removing all settings for the Turtlebot.
* **set-simulation** - this function will set the parameters required to run the Turtlebot simulation.

**ros2 run teleop\_twist\_keyboard teleop\_twist\_keyboard --ros-args -r \_\_ns:=/T10**

**ros2 launch turtlebot4\_navigation slam.launch.py namespace:=ROBOT\_NAMESPACE**

**ros2 launch turtlebot4\_viz view\_robot.launch.py namespace:=ROBOT\_NAMESPACE**

**ros2 launch turtlebot4\_navigation nav2.launch.py namespace:=ROBOT\_NAMESPACE**