

How to Create TurtleBot3 Simulation-ROS

1-install package dependences by the following commands

```
cd ~/catkin_ws/src/  
git clone https://github.com/ROBOTIS-GIT/turtlebot3_msgs.git  
git clone https://github.com/ROBOTIS-GIT/turtlebot3.git  
cd ~/catkin_ws && catkin_make
```

2-Type this command to open the bashrc file to add this setting

```
gedit ~/.bashrc
```

Open the file and write the following command “TurtleBot3 has 3 kinds Burger, Waffle, and Waffle Pi”

```
export TURTLEBOT3_MODEL=Waffle
```

Then save and close the file after that write the following command

```
source ~/.bashrc
```

3- download TurtleBot simulation files

```
cd ~/catkin_ws/src/  
git clone https://github.com/ROBOTIS-GIT/turtlebot3_simulations.git  
cd ~/catkin_ws && catkin_make
```

4-launch virtual robot by using RViz

```
roslaunch turtlebot3_fake turtlebot3_fake.launch
```

To move TurtleBot around screen use this command line in new terminal

```
roslaunch turtlebot3_teleop turtlebot3_teleop_key.launch
```

Resource: <https://automaticaddison.com/how-to-launch-the-turtlebot3-simulation-with-ros/#gazebo>

