teleop:

1. Turn on Turtlebot and laptop. Plug in USB
2. Open Terminal
3. Type roslaunch turtlebot\_bringup minimum.launch
4. Open new terminal (ctrl + shift + n)
5. Type relaunch turtlebot\_teleop keyboard\_teleop.launch
6. EXit ctrl + z

Mapping:

1. Everything on and plugged in. ….=tab
2. On robot minimal.launch
3. On robot roslaunch turtlebot\_navigation gmapping…
4. On work station roslaunch turtlebot\_rviz\_launchers view\_nav.<tab>
5. On robot rosrun map\_server map\_server-f “file location”