Official ROS Packages:

1. gmapping: With the gmapping_demo.launch file, you can easily perform SLAM and build a map of the environment with a robot equipped with laser range finder sensors or RGB-D cameras.
2. turtlebot_teleop: With the keyboard_teleop.launch file, you can manually control a robot using keyboard commands.
3. turtlebot_rviz_launchers: With the view_navigation.launch file, you can load a preconfigured rviz workspace. You'll save a lot of time by launching this file, because it will automatically load the robot model, trajectories, and map for you.
4. turtlebot_gazebo: With the turtlebot_world.launch you can deploy a turtlebot in a gazebo environment by linking the world file to it.

Additional nodes:

- wall_follower node: drives the robot autonomously to map the world
- pick_objects node: robot moves to desired position, picks up an object and delivers it to the desired drop off zone
- add_markers node: node subscribes to robot's odometry, keeps track of the robot's pose and publishes markers to rviz.