TASK:
Using SLAM map to launch the navigation

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Steps:

First I Lunch the Gazebo environment

> $ export TURTLEBOT3_MODEL=burger
> $ roslaunch turtlebot3_gazebo turtlebot3_house.launch

then Run Navigation Node:

> $ export TURTLEBOT3_MODEL=burger
> $ roslaunch turtlebot3_navigation turtlebot3_navigation.launch map_file:=$HOME/map.yaml

After running the navigation node I Estimating the Initial Pose by Clicking the 2D Pose Estimate button in the RViz menu, Then I located and dragged the large arrow many times until the LDS sensor data is overlayed on the saved map.

And now I Launch the keyboard teleoperation node:

> $ roslaunch turtlebot3_teleop turtlebot3_teleop_key.launch

Then Set Navigation Goal by

Clicking the 2D Nav Goal button in the RViz menu, then I Clicked on the map to set the destination of the robot and drag the arrow toward the direction where the robot will be facing.

Results: