__Steps__

source the work space then:

`export TURTLEBOT3_MODEL=burger`

`roslaunch turtlebot3_gazebo turtlebot3_house.launch`

then open anew terminal

`export TURTLEBOT3_MODEL=burger`

`roslaunch turtlebot3_slam turtlebot3_slam.launch`

open anew terminal

`export TURTLEBOT3_MODEL=burger`

`roslaunch turtlebot3_teleop turtlebot3_teleop_key.launch`

start moving in order to make the map then use this command to save your map for me it is saved in home

`rosrun map_server map_saver`

then in order to navigate autonomously use this command

`roslaunch turtlebot3_navigation turtlebot3_navigation.launch map_file:=$HOME/map.yaml`