Install Turtulebot 3

1. Open the terminal and write this code:

```
sudo apt-get update
sudo apt-get upgrade
wget https://raw.githubusercontent.com/ROBOTIS-
GIT/robotis_tools/master/install_ros_kinetic.sh && chmod 755 ./install_ros_kinetic.sh
&& bash ./install_ros_kinetic.sh
```

2. install dependent packages for TurtleBot3 control using this code”

```
sudo apt-get install ros-kinetic-joy ros-kinetic-teleop-twist-joy ros-kinetic-teleop-
twist-keyboard ros-kinetic-laser-proc ros-kinetic-rgbd-launch ros-kinetic-depthimage-
to-laserscan ros-kinetic-rosserial-arduino ros-kinetic-rosserial-python ros-kinetic-
rosserial-server ros-kinetic-rosserial-client ros-kinetic-rosserial-msgs ros-kinetic-
amcl ros-kinetic-map-server ros-kinetic-move-base ros-kinetic-urdf ros-kinetic-xacro
ros-kinetic-compressed-image-transport ros-kinetic-rqt-image-view ros-kinetic-
gmapping ros-kinetic-navigation ros-kinetic-interactive-markers
cd ~/catkin_ws/src/
git clone https://github.com/ROBOTIS-GIT/turtlebot3_msgs.git
git clone -b kinetic-devel https://github.com/ROBOTIS-GIT/turtlebot3.git
cd ~/catkin_ws && catkin_make
```

- after that we get nstall package and install turtlebot simulation package

3. launching turtlebot3 simulation

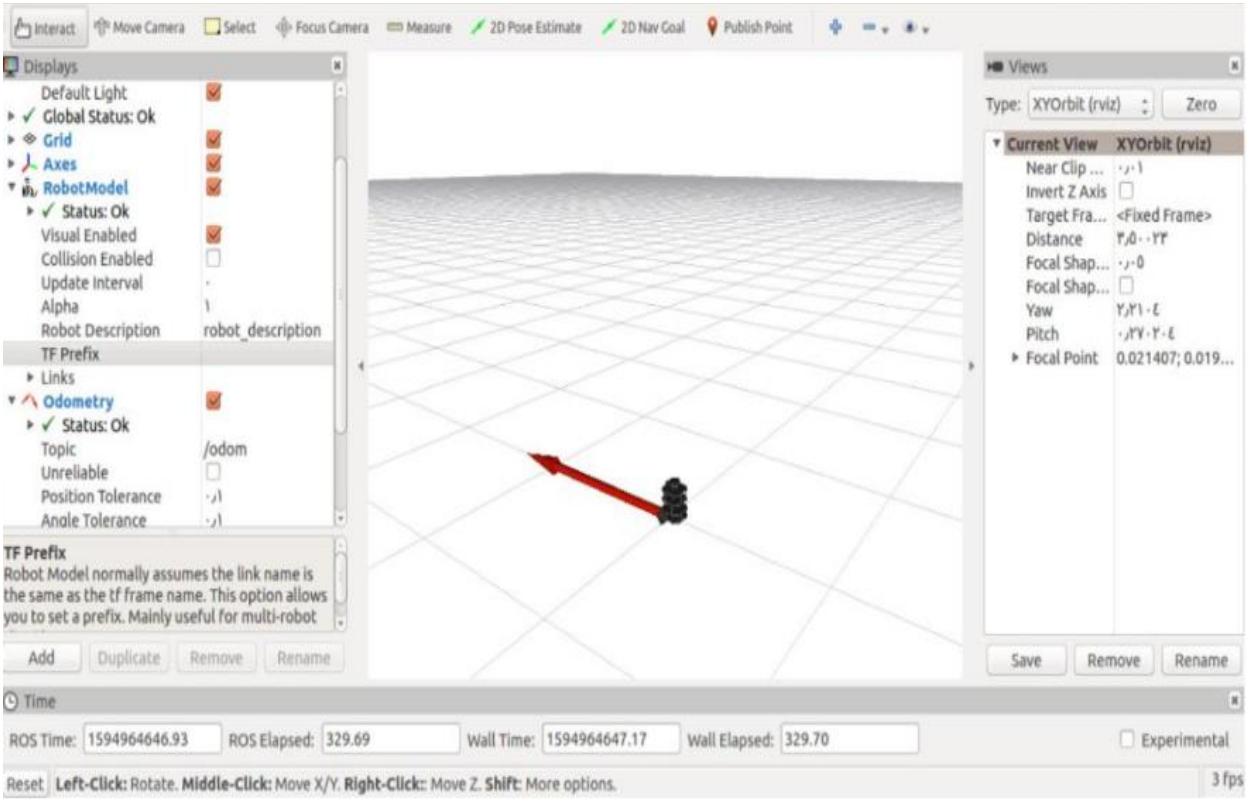
- open the terminal and write this code”

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

- then write this to lunching

```
export TURTLEBOT3_MODEL=burger
roslaunch turtlebot3_fake turtlebot3_fake.launch
```

The Output:


Interact
Move Camera
Select
Focus Camera
Measure
2D Pose Estimate
2D Nav Goal
Publish Point
Displays
Default Light
Global Status: Ok
Grid
Axes
RobotModel
Status: Ok
Visual Enabled
Collision Enabled
Update Interval
Alpha
Robot Description
robot_description
TF Prefix
Links
Odometry
Status: Ok
Topic
/odom
Unreliable
Position Tolerance
Angle Tolerance
TF Prefix
Robot Model normally assumes the link name is the same as the tf frame name. This option allows you to set a prefix. Mainly useful for multi-robot
Add
Duplicate
Remove
Rename
Views
Type: XYOrbit (rviz)
Zero
Current View
XYOrbit (rviz)
Near Clip ...
Invert Z Axis
Target Fra...
<Fixed Frame>
Distance
Focal Shap...
Focal Shap...
Yaw
Pitch
Focal Point
0.021407; 0.019...
Save
Remove
Rename
Time
ROS Time:
1594964646.93
ROS Elapsed:
329.69
Wall Time:
1594964647.17
Wall Elapsed:
329.70
Experimental
Reset
Left-Click: Rotate. Middle-Click: Move X/Y. Right-Click:: Move Z. Shift: More options.
3 fps