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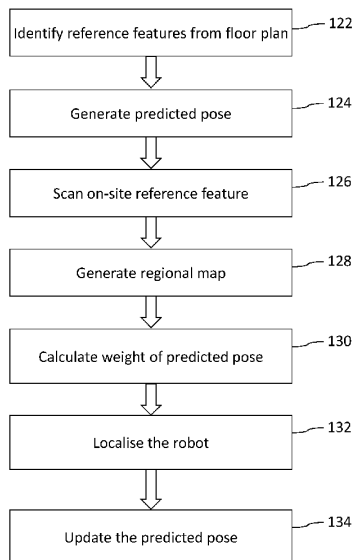


Fig. 3

(57) Abstract: Method and system for localising a robot 100 using a scale plan of a designated environment are provided herein. In an embodiment, the method comprises: identifying reference features from the scale plan 136; generating a predicted pose 156 of the robot's current location on the scale plan 136 based on the identified reference features; scanning on-site reference features 186 of the current location; generating a map 158 for the current location to localise the robot 100, based on the scanned on-site reference features 186 of the current location and last N frames of historical scans of previous on-site reference features 186 of a plurality of locations in the designated environment that the robot traversed through before reaching the current location; the last N frames being fewer than total frames of the historical scans of the previous on-site reference features 186.

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