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(71) Applicant: **AUGMENTUS PTE. LTD.** [SG/SG]; 1 Scotts Road, #24-10, Shaw Centre, Singapore 228208 (SG).

(72) Inventor: **LEONG, Yong Shin**; Blk 713 Woodlands Drive 70, #10-81, Singapore 730713 (SG).

(74) Agent: **AMICA LAW LLC**; 77 Robinson Road, #22-01 Robinson 77, Singapore 068896 (SG).

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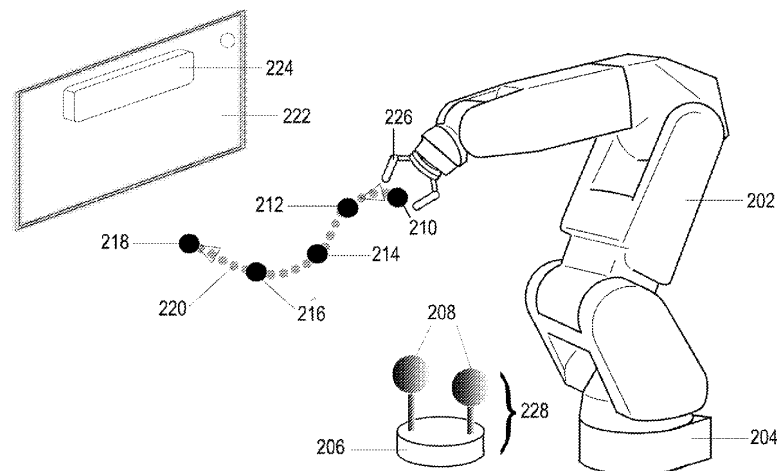


Figure 2

(57) Abstract: A method comprising identifying a robotic device and a calibration fixture in a vicinity of the robotic device; referencing the calibration fixture to a base of the robotic device to determine a first pose of the robotic device; receiving a 3D image of the environment, wherein the 3D image includes the calibration fixture; determining a second pose of the calibration fixture relative to the sensor; determining a third pose of the robotic device relative to the sensor based on the first pose and the second pose; receiving a plurality of trajectory points; determining a plurality of virtual trajectory points corresponding to the plurality of trajectory points based on the 3D image and the third pose; providing for display of the plurality of virtual trajectory points; and providing an interface for manipulating the virtual trajectory points.

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