ABSTRACT

COMPUTER-IMPLEMENTED METHOD

A computer-implemented method of configuring a robot is provided. The method comprises: receiving a first scan of a physical object from a first scanner, wherein the first scan includes a first 3D virtual representation of at least a portion of the physical object in a first coordinate system corresponding to a coordinate system of the robot; receiving a second scan of the physical object from a second scanner, wherein the second scan includes a second 3D virtual representation of at least a portion of the physical object in a second coordinate system; comparing the first and second 3D virtual representations to determine a coordinate transformation between the first and second coordinate systems; and using the transformation to align the first and second 3D virtual representations.

[To be published with **FIG. 4**]