

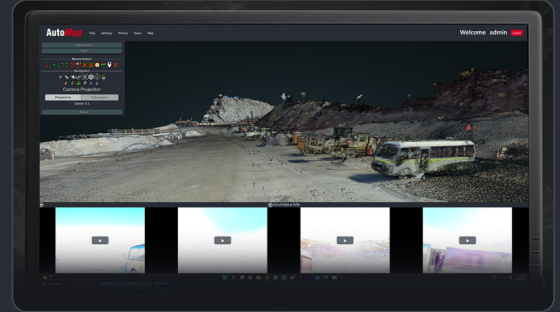
ORBISFUSE · BROWSER-BASED PLATFORM

# OrbisFuse

CHANGE DETECTION | AUTO CLEANING | UNLIMITED USERS

## On-premises server SLAM — retain control of your data.

Upload .ply or .las files and start viewing, sharing, and measuring within minutes. OrbisFuse is the complimentary cloud platform behind every VellusX and TerrusM capture — unlimited seats, automatic conversion, measurement and annotation tools built in.



THE ORBISFUSE VIEWER IN THE BROWSER

Designed to work wirelessly with all AutoMap systems: upload maps over WiFi **straight from the unit to the cloud** with no data loss, then explore and share the captured point clouds in a full 3D environment — connecting your team both on and off site.

∞

USER ACCOUNTS

**PLY/LAS**

UPLOAD FORMATS

**3D**

IN-BROWSER VIEWING

**On**

PREM OPTION

### CAPABILITIES

## View, share, and measure — all in the browser

#### In-cloud processing

Heavy SLAM and point-cloud computation runs on server-side compute, not your laptop. Registration, fusion, and map optimisation are offloaded — results come straight back.

#### Centralised access

Every capture lands in one authoritative store. Surveyors, engineers, and project managers open the same point cloud from anywhere in the world.

#### Choose your workflow

Assemble the processing steps each job needs — downsampling, noise filtering, registration and drift correction, segmentation and classification.

#### Automatic pipelining

Uploads flow straight into an automated pipeline: filtering, alignment, and .ply → .las/.laz conversion run in the background, standards-ready for your GIS tools.

#### Customisable algorithms

Plug in the algorithms your analysis depends on — feature extraction, segmentation, change detection, or your own classifiers — tuned per project.

#### On-premises management

Run the whole platform inside your own network. Full sovereignty over storage, access, and audit logging — built for defence, mining, and government work.

### Powered by **Wildcat** SLAM

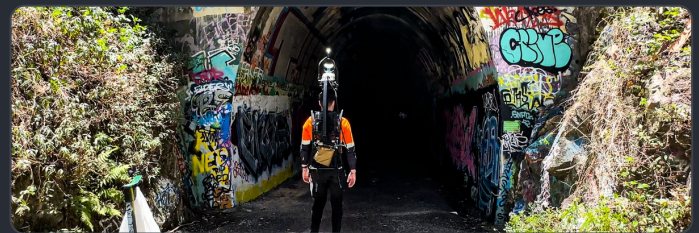
OrbisFuse runs the same CSIRO-developed **WildcatSLAM** engine as every AutoMap scanner, scaled up to server hardware. The engine is fully multi-threaded with **no upper limit** on simultaneous threads — processing speed scales directly with your compute.

**PLATFORM CAPABILITIES**

DEPLOYMENT	Cloud-hosted or on-premises
ACCESS	Web browser, SSL (port 443)
USER ACCOUNTS	Unlimited
INPUT FORMATS	PLY, LAS
CONVERSION	Automatic .ply → .las / .laz
MEASUREMENT	Distance & volumetrics
ANNOTATION	Notes, mark-ups, sharing
ORGANISATION	Semantic map categories
CHANGE DETECTION	Basemap change mapping
CLEANING	Auto point-cloud cleaning
DEVICE UPLOAD	VellusX & TerrusM over WiFi
ENGINE	Unlimited-thread WildcatSLAM

**RECOMMENDED SERVER (ON-PREM)**

CPU	AMD Threadripper 7980X+
RAM	≥ 256 GB (1 h+ maps need more)
SWAP	Dedicated 2 TB SSD
STORAGE	≥ 18 TB, ~200 GB per hour
REDUNDANCY	RAID 1 min, RAID 10 ideal
NETWORK	Gigabit scanner link; WiFi



• CAPTURE IN THE FIELD – REVIEW IN THE BROWSER



• COLOURISED STREETSCAPE – MEASURED &amp; SHARED IN ORBISFUSE

01

**Upload**

Stream a capture straight from VellusX or TerrusM — or drag a .ply / .las in from the desktop.

02

**Collaborate**

Share a link. Teammates annotate, measure, and discuss the same point cloud in the browser.

03

**Decide**

Verify site progress, validate compliance, or hand the data off downstream — all from one workspace.

**APPLICATIONS**

• Plant digitization

• Underground mapping

• Road scanning

• Building documentation

• Shaft inspection

• AEC

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**ECOSYSTEM**

Feed it with **VellusX** for GPS-fused capture, or **TerrusM** for harsh environments.

