

set_model_pose_algorithm

Overview

This command sets the method such as 6DOF or Inverse Kinematics for computing model pose. This command can be found under **Model Building** in the pipeline workshop. This command should be set before computing your desired model building. It is good practice to RECALC after this command.

Pipeline Command

The command below is as seen on the Visual3D application.

```
Set_Model_Pose_Algorithm
! /CALIBRATION_FILE=
! /ALGORITHM=6DOF
! /OPTIMIZER=
! /FIT_CALIBRATION_FILE=TRUE
! /START_WITH_SIMULATED_ANNEALING=FALSE
! /F_TOLERANCE=1e-12
! /X_TOLERANCE=1e-12
! /G_TOLERANCE=1e-12
! /IK_USE_ALL_FRAMES=true
! /IK_EVENT_SEQUENCE=
;
```

Command Parameters

The following table shows the command parameters and descriptions:

CALIBRATION_FILE	The name of the hybrid model. Use the full pathname.
ALGORITHM	Pose Algorithm to set 6DOF is default or can change to Inverse Kinematics
OPTIMIZER	Set optimizer to one of QUASI_NEWTON, LEVENBERG_MARQUARDT or LBFGSB
FIT_CALIBRATION_FILE	TRUE or FALSE fit the calibration trial
START_WITH_SIMULATED_ANNEALING	TRUE FALSE to generate an initial solution before optimization using simulated annealing
F_TOLERANCE	Convergence tolerance for the objective function. Default e-12
X_TOLERANCE	Convergence tolerance for optimization variables. Default e-12
G_TOLERANCE	Convergence tolerance for the function gradient. Default e-12
IK_USE_ALL_FRAMES	TRUE or FALSE use all frames for Inverse Kinematics calculations
IK_EVENT_SEQUENCE	Define and Event sequence for Inverse Kinematics calculations

Examples

Setting the model pose to Inverse Kinematics with a LEVENBERG_MARQUARDT optimizer.

```
! Method For Computing Model Pose
!
Set_Model_Pose_Algorithm
! /CALIBRATION_FILE=
/ALGORITHM=Inverse Kinematics
/OPTIMIZER=LEVENBERG_MARQUARDT
/FIT_CALIBRATION_FILE=FALSE
! /START_WITH_SIMULATED_ANNEALING=FALSE
! /F_TOLERANCE=1e-12
! /X_TOLERANCE=1e-12
! /G_TOLERANCE=1e-12
! /IK_USE_ALL_FRAMES=true
! /IK_EVENT_SEQUENCE=
:
```

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