

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.

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	...
START_WITH_SIMULATED_ANNEALING	...
_TOLERANCE	F, G, and X Tolerance
IK_USE_ALL_FRAMES	[]
IK_EVENT_SEQUENCE	[]

Dialog

The command can be edited in a text editor or in a dialog form. To edit in the dialog pop up form either click on the **Edit** button in the pipeline workshop or double-click on the pipeline command. The dialog is shown below.

Examples

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Simple example

- Image or dialog box

- Brief description of components (Combo boxes, acronyms, etc.)

Showing functionality of the command, using a diagram possibly to show output.

Complex example

Combine with other commands and show step-by-step process for frequent use case

Notes

- Important considerations (anything included in the page before the reformat)

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