

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	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	
IK_USE_ALL_FRAMES	[]	
IK_EVENT_SEQUENCE	[]	

Examples

Last update: 2026/06/17 18:34 visual3d:documentation:pipeline:other_commands:set_model_pose_algorithm https://has-motion.com/wiki/doku.php?id=visual3d:documentation:pipeline:other_commands:set_model_pose_algorithm&rev=1781721272

Simple example Dialog

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

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.

Complex example

- Image of dialog box

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

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

Notes

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

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