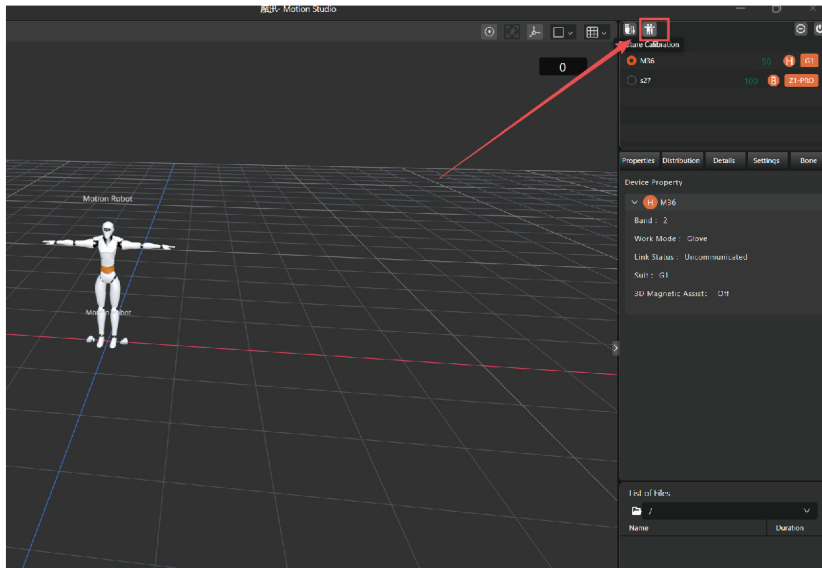


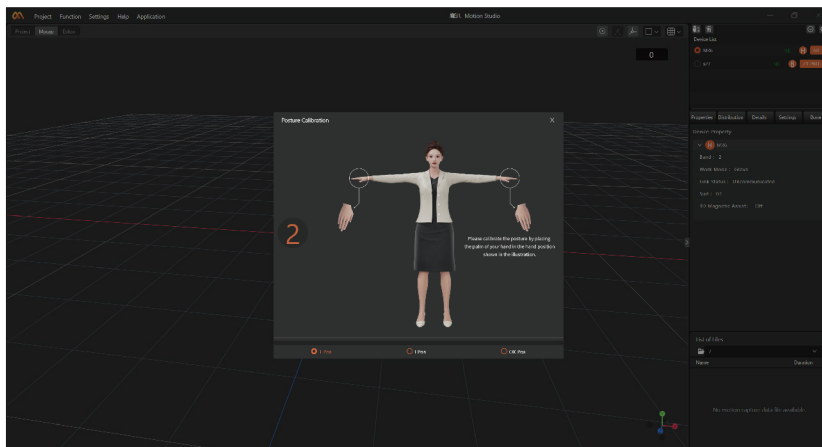
4.2.4 Pose Calibration

After wearing all sensors correctly, click the [Pose Calibration] button and follow the on-screen instructions to perform pose calibration. The specific requirements for each pose are as follows:



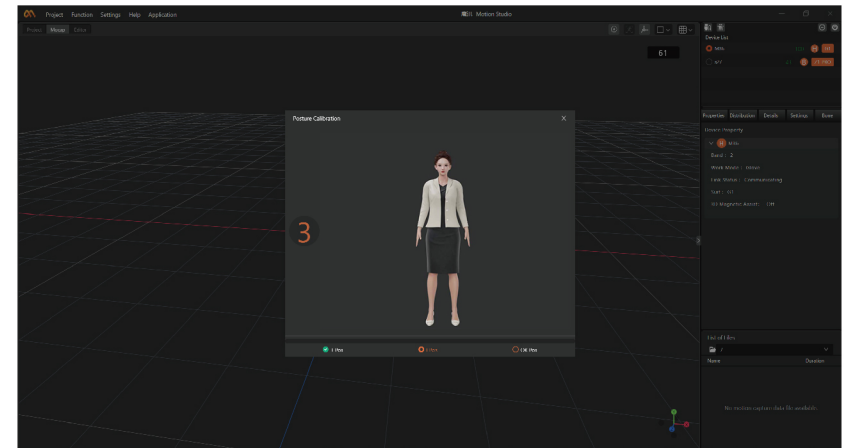
T-Pose

- Stand upright with both feet together. Extended both arms and horizontally to the sides, perpendicular to the body, with palms facing downward;
- Extended all fingers and keep together.



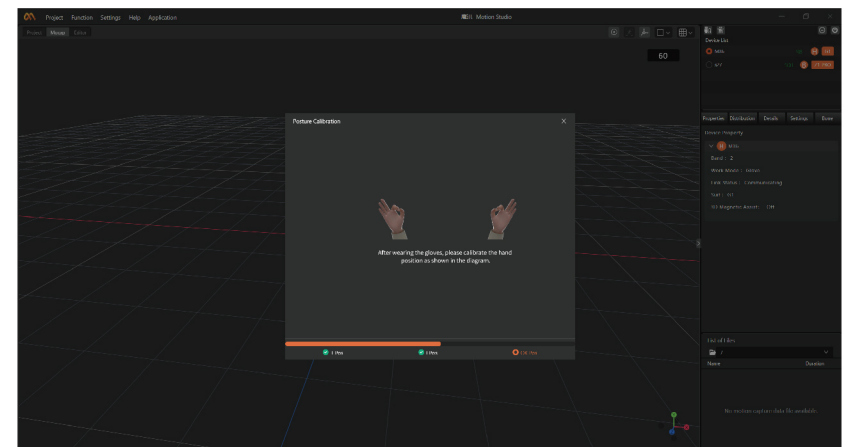
T-Pose

- Stand upright with both feet together;
- Let both arms hang naturally at the sides, palms facing inward. Keep fingers extended, with thumbs pointing toward the outside of the thighs;
- Look straight ahead, with the chin parallel to the ground;
- Keep shoulders relaxed and avoid shrugging.



OK-Pose

- Hold both hands approximately 30 cm (11.8in) in front of the chest;
- Form an “OK” gesture with both hands.

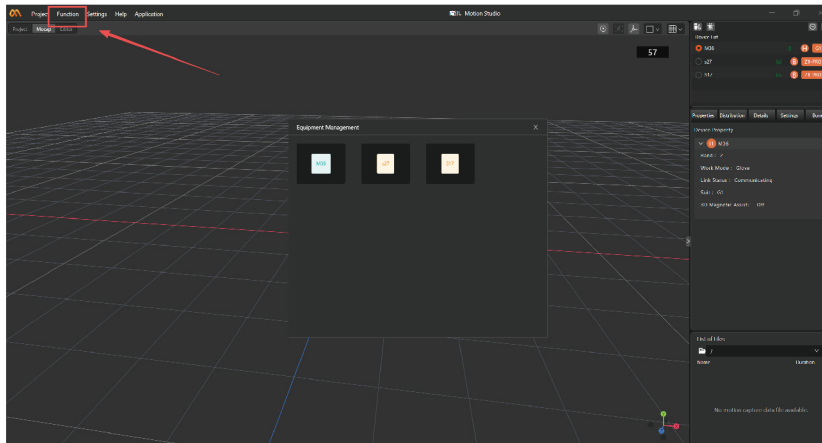


*Calibration Principle

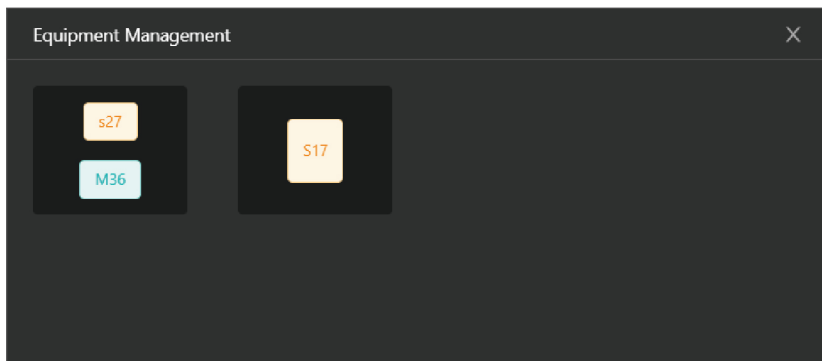
In inertial motion capture systems, pose calibration is used to establish the mapping relationship between sensor coordinates and the human body skeletal model. The accuracy and standardization of calibration poses directly affect motion tracking precision, stability of the skeletal model or overall motion capture quality. Users are strongly advised to follow both textual instructions and visual guides carefully.

4.2.5 Device Pairing

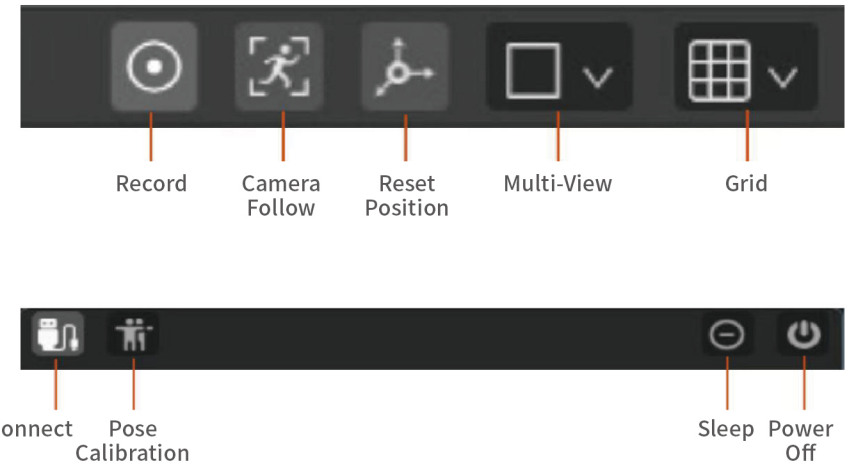
When multiple sets of glove devices and full-body devices are connected, users may select **Device Management** from the function menu to freely pair glove devices with full-body devices.



After combination, the Device Management interface will be displayed accordingly:

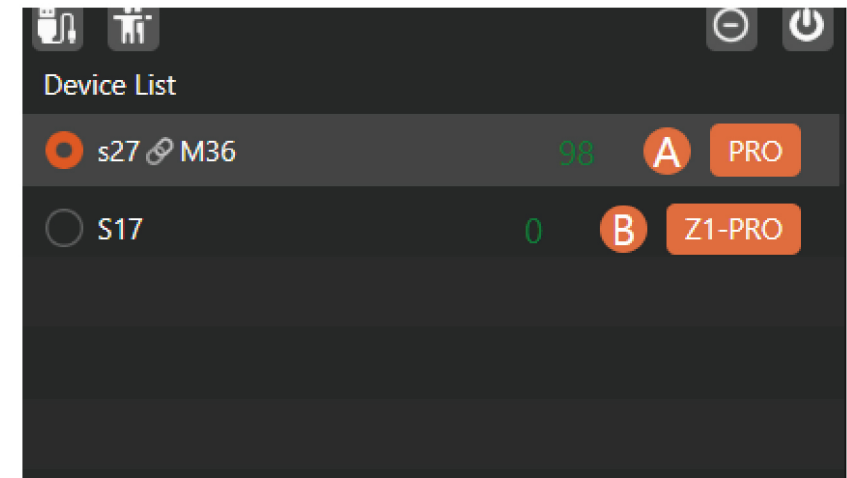


4.3 Function Description

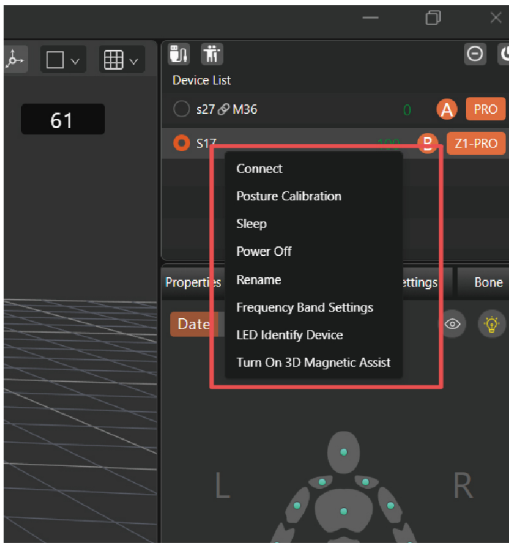


4.3.1 Device List

The **Device List** displays all devices currently connected to the system.

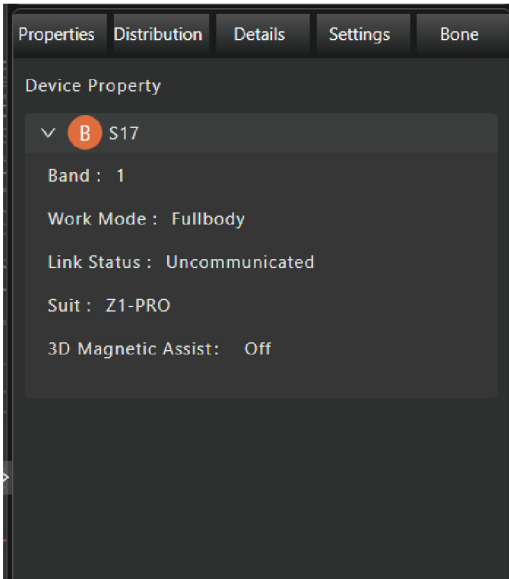


Select a device and right-click to perform individual operations such as **Connect**, **Pose Calibration**, and other device-specific actions.



4.3.2 Device Properties

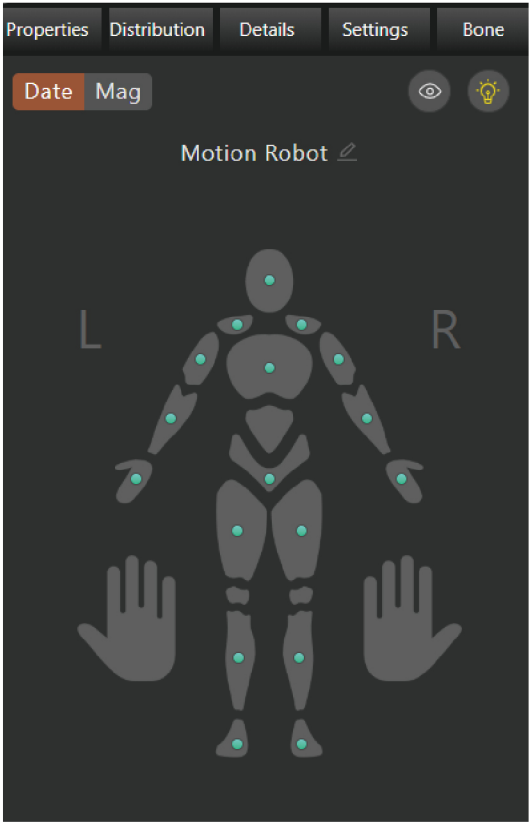
Detailed information for the selected device will be displayed, including frequency band, working mode, communication status and device type.



4.3.3 Sensor Distribution

Displays the packet reception rate and magnetic environment status of each sensor node. Indicator Meanings:

- **Green**: Normal;
- **Orange**: Acceptable;
- **Red**: Poor;
- **Gray**: Not connected. Please check the connection between the sensor and the charging case.



4.3.4 Device Details

Displays detailed information for each sensor, including: packet reception rate, magnetic environment status and battery level.

Properties	Distribution	Details	Settings	Bone
Sensor	Number	Signal	Magnetic	Power
Head	01	100%	Poor	59
LeftShoulder	02	85%	Fair	79
RightShoulder	03	100%	Fair	87
LeftUpperArm	04	100%	Poor	100
Spine	05	100%	Good	90
RightUpperArm	06	100%	Good	59
LeftLowerArm	07	100%	Good	91
Crotch	08	100%	Fair	30
RightLowerArm	09	100%	Fair	80
LeftHand	10	100%	Fair	99
RightHand	11	100%	Fair	100
LeftUpperLeg	12	98%	Good	71
RightUpperLeg	13	100%	Fair	94
LeftLowerLeg	14	100%	Good	69
RightLowerLeg	15	98%	Fair	100
LeftFoot	16	100%	Fair	90
RightFoot	17	100%	Poor	99

4.3.5 Parameter Settings

Allows users to configure parameters according to different application scenarios.

PropertiesDistributionDetailsSettingsBone

Application Scenarios

Ground

Touchdown point

☒ Adaptive☐ Foot☐ Crotch☐ Hand

Constraint Mode

Normal

Joint Constraint

0.30

Yaw

0

Pitch

0

Model Initial Position

X0m

Y0m

Apply

Application Scenarios

- Flat Ground:** Suitable for standard motion capture on flat surfaces.
- Stair Climbing:** Used for vertical or uneven movement scenarios
- Hip Lock:** Locks the hip position of the virtual character
- In-Place(Beta):** Reduces positional drift during small-area movements.(recommended for virtual production or live streaming)

Contact Points

Before starting motion capture, users can predefine which body part (hand, foot, or hip) will contact the ground or a fixed surface, depending on the intended motion scenario. In most cases, foot contact is selected by default, as it provides the most stable reference for general motion capture tasks.

Heading Angle

The Heading Angle is used to adjust the yaw direction of the virtual character model. This parameter can also be utilized in third-party software to directly control the facing direction of the character.

Pitch Angle

The Pitch Angle controls the forward and backward tilt of the virtual character model. If the character appears to lean excessively forward, increase the pitch value slightly; If the character leans backward, decrease the value accordingly to achieve a balanced posture.

4.3.6 Skeleton Adjustment

Allows users to customize skeletal dimension templates.

PropertiesDistributionDetailsSettingsBone

Bone Size (unit: cm)

Template

male170

Head

15.95

Neck

9.47

Shoulder Width

32.00

Body

55.84

Upper Arm

26.50

Forearm

26.00

Palm

17.50

Hip Width

18.50

Upper Leg

41.87

Lower Leg

41.87

Heel Height

7.69

Foot Length

25.00

Save