This is supplementary material to my video on Swapping Markers/Cleaning Gaps (3.3.1 Used on data captured in 2.5)

Swapping Markers



Covariance Error is indicated by the grey circles – overlapping circles usually indicate a swapped marker Large circles indicate occlusion

In this case, the hands are swapped – you can see that from the criss cross (should be a box)

This is reconstruction with Camera Trajectory set to 3



Be aware that the reconstruction settings matter: Camera Tragectory 3 on left 2 on the right NOTE: In 3.3.1 we are getting much better data – this data is provided for the purposes of teaching clean up.





Uncorrected hand

Corrected hand

Once you see a problem, fix it and then re-calibrate. Here is what it would look like at the solving stage





Uncorrected hand

Corrected hand

For your first Exercise you will only be cleaning in blade (Motion Builder is the next Exercise, but here is what it would look like on a character)



Labeling (creating the vsk) – result of

1. Reconstruct/ 2. Create Labeling Setup /3. Label ROM / 4. Calibrate





Swap markers is under the Labeling Tab. Use Alt to select – may want to change the Selection Filters to Marker – note this is swapped now but still needs re-calibration

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It is now re-calibrated and now you would clean up any other major problems and move on to solving. This is for a ROM but the same techniques can be applied to takes, however keep in mind you are no longer using the Labeling and Solving menus.

Filling Gaps



Using the **Marker Editing** tool, select the marker with problem and press Find Next Gap (best to create another pane showing Graph)





Go to just before the marker disappeared (use the arrows)

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Alt select the range and also 2 other markers (Alt/Ctrl select) and then Fill Rigid Remember to calibrate after

٥ _ × Manipulating the Skeleton



Change your Selection Filters to **SolvingBone** and **Alt** select – select the manipulator tool of the left menu and hold **Ctrl** to move to new position

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Be sure to Update Constraint Offset and solve All Frames