

Left stereo image

Right stereo image

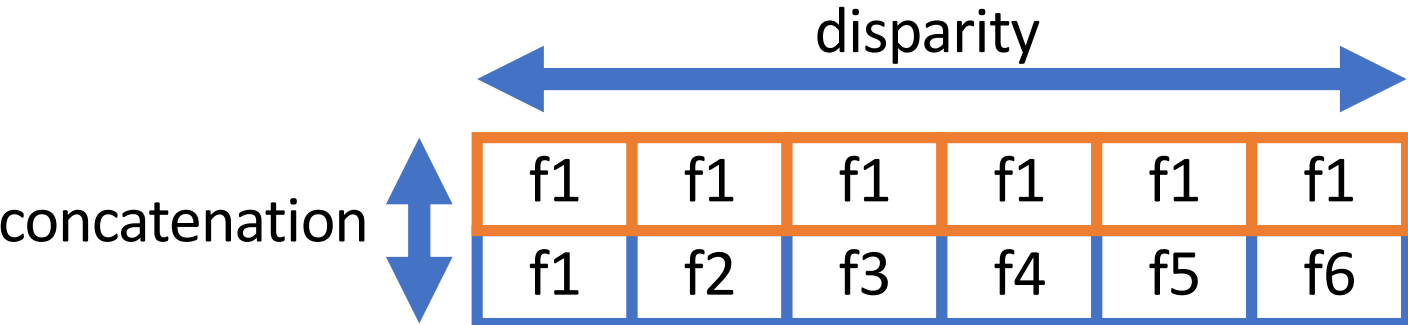
Input image



2-D convolutions



Cost volume



3-D convolutions



Disparity estimation

