JavaScript is disabled on your browser.

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* [Next Class](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html)
* [Frames](http://docs.google.com/index.html?org/opencv/calib3d/StereoBM.html)
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org.opencv.calib3d

## Class StereoBM

* java.lang.Object
  + [org.opencv.core.Algorithm](http://docs.google.com/org/opencv/core/Algorithm.html)
    - [org.opencv.calib3d.StereoMatcher](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html)
      * org.opencv.calib3d.StereoBM
* public class StereoBM  
  extends [StereoMatcher](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html)  
  Class for computing stereo correspondence using the block matching algorithm, introduced and contributed to OpenCV by K. Konolige.

### Field SummaryFields

| Modifier and Type | Field and Description |
| --- | --- |
| static int | [**PREFILTER\_NORMALIZED\_RESPONSE**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#PREFILTER_NORMALIZED_RESPONSE) |
| static int | [**PREFILTER\_XSOBEL**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#PREFILTER_XSOBEL) |

### Fields inherited from class org.opencv.calib3d.[**StereoMatcher**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html)[DISP\_SCALE](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#DISP_SCALE), [DISP\_SHIFT](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#DISP_SHIFT)

### Method SummaryMethods

| Modifier and Type | Method and Description |
| --- | --- |
| static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) | [**\_\_fromPtr\_\_**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#__fromPtr__(long))(long addr) |
| static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) | [**create**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#create())() Creates StereoBM object disparity from 0 (default minimum disparity) to numDisparities. |
| static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) | [**create**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#create(int))(int numDisparities) Creates StereoBM object |
| static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) | [**create**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#create(int,%20int))(int numDisparities, int blockSize) Creates StereoBM object |
| int | [**getPreFilterCap**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getPreFilterCap())() |
| int | [**getPreFilterSize**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getPreFilterSize())() |
| int | [**getPreFilterType**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getPreFilterType())() |
| [Rect](http://docs.google.com/org/opencv/core/Rect.html) | [**getROI1**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getROI1())() |
| [Rect](http://docs.google.com/org/opencv/core/Rect.html) | [**getROI2**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getROI2())() |
| int | [**getSmallerBlockSize**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getSmallerBlockSize())() |
| int | [**getTextureThreshold**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getTextureThreshold())() |
| int | [**getUniquenessRatio**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#getUniquenessRatio())() |
| void | [**setPreFilterCap**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setPreFilterCap(int))(int preFilterCap) |
| void | [**setPreFilterSize**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setPreFilterSize(int))(int preFilterSize) |
| void | [**setPreFilterType**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setPreFilterType(int))(int preFilterType) |
| void | [**setROI1**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setROI1(org.opencv.core.Rect))([Rect](http://docs.google.com/org/opencv/core/Rect.html) roi1) |
| void | [**setROI2**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setROI2(org.opencv.core.Rect))([Rect](http://docs.google.com/org/opencv/core/Rect.html) roi2) |
| void | [**setSmallerBlockSize**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setSmallerBlockSize(int))(int blockSize) |
| void | [**setTextureThreshold**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setTextureThreshold(int))(int textureThreshold) |
| void | [**setUniquenessRatio**](http://docs.google.com/org/opencv/calib3d/StereoBM.html#setUniquenessRatio(int))(int uniquenessRatio) |

### Methods inherited from class org.opencv.calib3d.[**StereoMatcher**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html)[compute](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#compute(org.opencv.core.Mat,%20org.opencv.core.Mat,%20org.opencv.core.Mat)), [getBlockSize](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getBlockSize()), [getDisp12MaxDiff](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getDisp12MaxDiff()), [getMinDisparity](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getMinDisparity()), [getNumDisparities](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getNumDisparities()), [getSpeckleRange](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getSpeckleRange()), [getSpeckleWindowSize](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getSpeckleWindowSize()), [setBlockSize](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setBlockSize(int)), [setDisp12MaxDiff](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setDisp12MaxDiff(int)), [setMinDisparity](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setMinDisparity(int)), [setNumDisparities](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setNumDisparities(int)), [setSpeckleRange](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setSpeckleRange(int)), [setSpeckleWindowSize](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setSpeckleWindowSize(int))

### Methods inherited from class org.opencv.core.[**Algorithm**](http://docs.google.com/org/opencv/core/Algorithm.html)[clear](http://docs.google.com/org/opencv/core/Algorithm.html#clear()), [empty](http://docs.google.com/org/opencv/core/Algorithm.html#empty()), [getDefaultName](http://docs.google.com/org/opencv/core/Algorithm.html#getDefaultName()), [getNativeObjAddr](http://docs.google.com/org/opencv/core/Algorithm.html#getNativeObjAddr()), [save](http://docs.google.com/org/opencv/core/Algorithm.html#save(java.lang.String))

### Methods inherited from class java.lang.Objectequals, getClass, hashCode, notify, notifyAll, toString, wait, wait, wait

### Field Detail

#### PREFILTER\_NORMALIZED\_RESPONSE public static final int PREFILTER\_NORMALIZED\_RESPONSESee Also:[Constant Field Values](http://docs.google.com/constant-values.html#org.opencv.calib3d.StereoBM.PREFILTER_NORMALIZED_RESPONSE)

#### PREFILTER\_XSOBEL public static final int PREFILTER\_XSOBELSee Also:[Constant Field Values](http://docs.google.com/constant-values.html#org.opencv.calib3d.StereoBM.PREFILTER_XSOBEL)

### Method Detail

#### \_\_fromPtr\_\_ public static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) \_\_fromPtr\_\_(long addr)

#### create public static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) create() Creates StereoBM object disparity from 0 (default minimum disparity) to numDisparities. The search range can then be shifted by changing the minimum disparity. (as the block is centered at the current pixel). Larger block size implies smoother, though less accurate disparity map. Smaller block size gives more detailed disparity map, but there is higher chance for algorithm to find a wrong correspondence. The function create StereoBM object. You can then call StereoBM::compute() to compute disparity for a specific stereo pair.Returns:automatically generated

#### create public static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) create(int numDisparities) Creates StereoBM objectParameters:numDisparities - the disparity search range. For each pixel algorithm will find the best disparity from 0 (default minimum disparity) to numDisparities. The search range can then be shifted by changing the minimum disparity. (as the block is centered at the current pixel). Larger block size implies smoother, though less accurate disparity map. Smaller block size gives more detailed disparity map, but there is higher chance for algorithm to find a wrong correspondence. The function create StereoBM object. You can then call StereoBM::compute() to compute disparity for a specific stereo pair. Returns:automatically generated

#### create public static [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html) create(int numDisparities, int blockSize) Creates StereoBM objectParameters:numDisparities - the disparity search range. For each pixel algorithm will find the best disparity from 0 (default minimum disparity) to numDisparities. The search range can then be shifted by changing the minimum disparity.blockSize - the linear size of the blocks compared by the algorithm. The size should be odd (as the block is centered at the current pixel). Larger block size implies smoother, though less accurate disparity map. Smaller block size gives more detailed disparity map, but there is higher chance for algorithm to find a wrong correspondence. The function create StereoBM object. You can then call StereoBM::compute() to compute disparity for a specific stereo pair. Returns:automatically generated

#### getPreFilterCap public int getPreFilterCap()

#### getPreFilterSize public int getPreFilterSize()

#### getPreFilterType public int getPreFilterType()

#### getROI1 public [Rect](http://docs.google.com/org/opencv/core/Rect.html) getROI1()

#### getROI2 public [Rect](http://docs.google.com/org/opencv/core/Rect.html) getROI2()

#### getSmallerBlockSize public int getSmallerBlockSize()

#### getTextureThreshold public int getTextureThreshold()

#### getUniquenessRatio public int getUniquenessRatio()

#### setPreFilterCap public void setPreFilterCap(int preFilterCap)

#### setPreFilterSize public void setPreFilterSize(int preFilterSize)

#### setPreFilterType public void setPreFilterType(int preFilterType)

#### setROI1 public void setROI1([Rect](http://docs.google.com/org/opencv/core/Rect.html) roi1)

#### setROI2 public void setROI2([Rect](http://docs.google.com/org/opencv/core/Rect.html) roi2)

#### setSmallerBlockSize public void setSmallerBlockSize(int blockSize)

#### setTextureThreshold public void setTextureThreshold(int textureThreshold)

#### setUniquenessRatio public void setUniquenessRatio(int uniquenessRatio)

* [Overview](http://docs.google.com/overview-summary.html)
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* Class
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* [Index](http://docs.google.com/index-all.html)
* [Help](http://docs.google.com/help-doc.html)
* [Prev Class](http://docs.google.com/org/opencv/calib3d/Calib3d.html)
* [Next Class](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html)
* [Frames](http://docs.google.com/index.html?org/opencv/calib3d/StereoBM.html)
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