JavaScript is disabled on your browser.

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org.opencv.calib3d

## Class StereoMatcher

* java.lang.Object
  + [org.opencv.core.Algorithm](http://docs.google.com/org/opencv/core/Algorithm.html)
    - org.opencv.calib3d.StereoMatcher
* Direct Known Subclasses: [StereoBM](http://docs.google.com/org/opencv/calib3d/StereoBM.html), [StereoSGBM](http://docs.google.com/org/opencv/calib3d/StereoSGBM.html)  
    
  public class StereoMatcher  
  extends [Algorithm](http://docs.google.com/org/opencv/core/Algorithm.html)  
  The base class for stereo correspondence algorithms.

### Field SummaryFields

| Modifier and Type | Field and Description |
| --- | --- |
| static int | [**DISP\_SCALE**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#DISP_SCALE) |
| static int | [**DISP\_SHIFT**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#DISP_SHIFT) |

### Method SummaryMethods

| Modifier and Type | Method and Description |
| --- | --- |
| static [StereoMatcher](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html) | [**\_\_fromPtr\_\_**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#__fromPtr__(long))(long addr) |
| void | [**compute**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#compute(org.opencv.core.Mat,%20org.opencv.core.Mat,%20org.opencv.core.Mat))([Mat](http://docs.google.com/org/opencv/core/Mat.html) left, [Mat](http://docs.google.com/org/opencv/core/Mat.html) right, [Mat](http://docs.google.com/org/opencv/core/Mat.html) disparity) Computes disparity map for the specified stereo pair |
| int | [**getBlockSize**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getBlockSize())() |
| int | [**getDisp12MaxDiff**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getDisp12MaxDiff())() |
| int | [**getMinDisparity**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getMinDisparity())() |
| int | [**getNumDisparities**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getNumDisparities())() |
| int | [**getSpeckleRange**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getSpeckleRange())() |
| int | [**getSpeckleWindowSize**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#getSpeckleWindowSize())() |
| void | [**setBlockSize**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setBlockSize(int))(int blockSize) |
| void | [**setDisp12MaxDiff**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setDisp12MaxDiff(int))(int disp12MaxDiff) |
| void | [**setMinDisparity**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setMinDisparity(int))(int minDisparity) |
| void | [**setNumDisparities**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setNumDisparities(int))(int numDisparities) |
| void | [**setSpeckleRange**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setSpeckleRange(int))(int speckleRange) |
| void | [**setSpeckleWindowSize**](http://docs.google.com/org/opencv/calib3d/StereoMatcher.html#setSpeckleWindowSize(int))(int speckleWindowSize) |

### 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

#### DISP\_SCALE public static final int DISP\_SCALESee Also:[Constant Field Values](http://docs.google.com/constant-values.html#org.opencv.calib3d.StereoMatcher.DISP_SCALE)

#### DISP\_SHIFT public static final int DISP\_SHIFTSee Also:[Constant Field Values](http://docs.google.com/constant-values.html#org.opencv.calib3d.StereoMatcher.DISP_SHIFT)

### Method Detail

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

#### compute public void compute([Mat](http://docs.google.com/org/opencv/core/Mat.html) left, [Mat](http://docs.google.com/org/opencv/core/Mat.html) right, [Mat](http://docs.google.com/org/opencv/core/Mat.html) disparity) Computes disparity map for the specified stereo pairParameters:left - Left 8-bit single-channel image.right - Right image of the same size and the same type as the left one.disparity - Output disparity map. It has the same size as the input images. Some algorithms, like StereoBM or StereoSGBM compute 16-bit fixed-point disparity map (where each disparity value has 4 fractional bits), whereas other algorithms output 32-bit floating-point disparity map.

#### getBlockSize public int getBlockSize()

#### getDisp12MaxDiff public int getDisp12MaxDiff()

#### getMinDisparity public int getMinDisparity()

#### getNumDisparities public int getNumDisparities()

#### getSpeckleRange public int getSpeckleRange()

#### getSpeckleWindowSize public int getSpeckleWindowSize()

#### setBlockSize public void setBlockSize(int blockSize)

#### setDisp12MaxDiff public void setDisp12MaxDiff(int disp12MaxDiff)

#### setMinDisparity public void setMinDisparity(int minDisparity)

#### setNumDisparities public void setNumDisparities(int numDisparities)

#### setSpeckleRange public void setSpeckleRange(int speckleRange)

#### setSpeckleWindowSize public void setSpeckleWindowSize(int speckleWindowSize)

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