

# Coding Assignment Report: Disparity map

Sourav Karmakar

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## Description of methods used

### 1 `cv2.StereoBM_create()`

For computing the stereo we have used `cv2.StereoBM_create()` method with a block size of 5 and number of disparity 16. We have used the `stereo.compute(imgL, imgR)` function by passing the left and right images, to compute the actual disparity. We have normalized and visualised in the figures given below. For each pixel algorithm will find the best disparity from 0 (default minimum disparity) to `numDisparities`.

### 2 `compute()`

Computes disparity map for the specified stereo pair.

## Disparity Map of Stereo Images

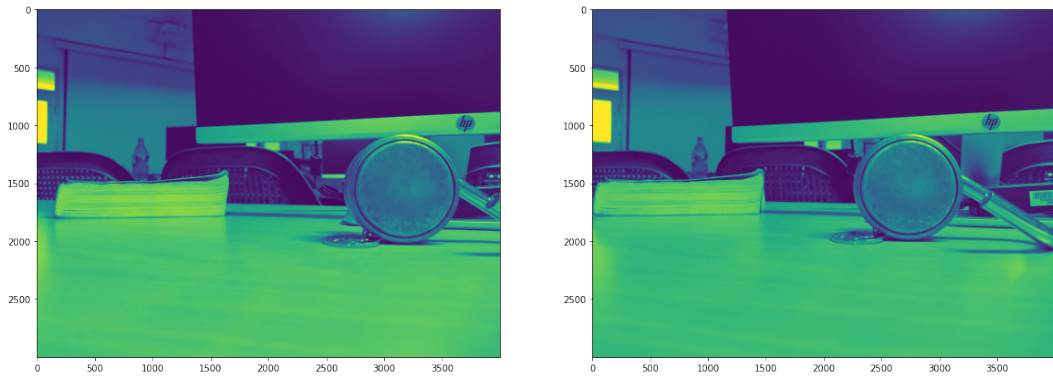


Figure 1: Two images where image-plane parallel to the scene

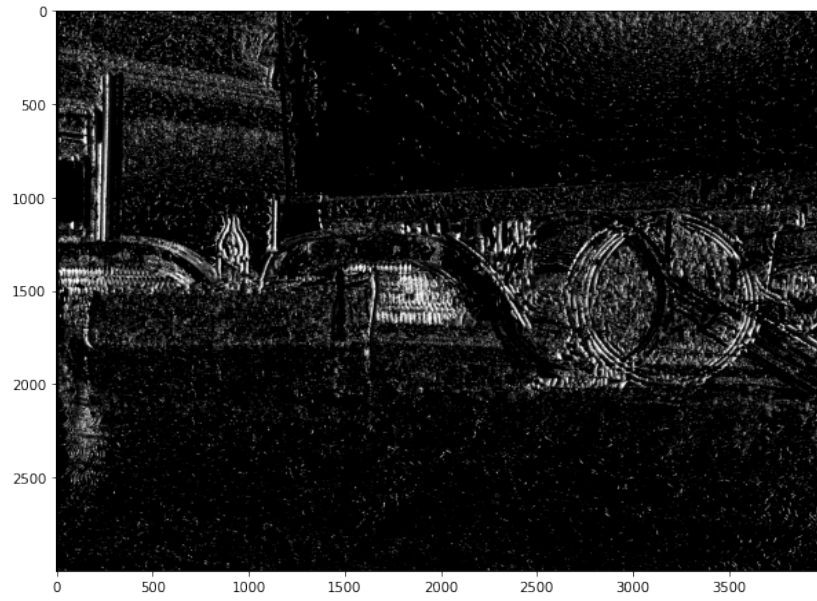


Figure 2: Disparity map