**Computer Vision - 217**

**Homework 2**

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**Answers for questions:**

**Section A:**

* No questions in this section to answer

**Section B:**

* No questions in this section to answer

**Section C:**

**Question E:**

Since we calculated the disparity map only on X axis we defined D2d(:,:,1)=0 because we don’t want to change anything in Y axis.

**Question H:**

…..need to complete

**Question I:**

The regions where there is a change in depth have more errors since there is more noise and uncertainty

**Documentation of the function**

**Section B:**

* Stereo:
  + Function sign:
    - [P] = stereo\_list(ps1,ps2, ML,MR)
  + Input parameters:
    - Ps1 – list of points in 2d
    - Ps2 – list of points in 2d
    - ML – projection matrix for left image
    - MR – projection matrix for right image
  + Output parameters:
    - List of points in 3d that represent the corresponding points in 2d
  + The function is located in the file stereo\_list .m

**Section C:**

* Disparity calculation:
  + Function sign:
    - [D] = disparityCalc(im1, im2,Sx,Sy,d\_min, d\_max)
  + Input params:
    - im1 – input image #1
    - im2– input image #2
    - Sx – patch size in x axis
    - Sy – patch size in y axis
    - d\_min – the beginning of the range to find corresponding pixel
    - d\_max – the end of the range to find corresponding pixel
  + Output params:
    - matrix D that consists of the disparity of each pixel
  + The function is located in the file disparityCalc.m