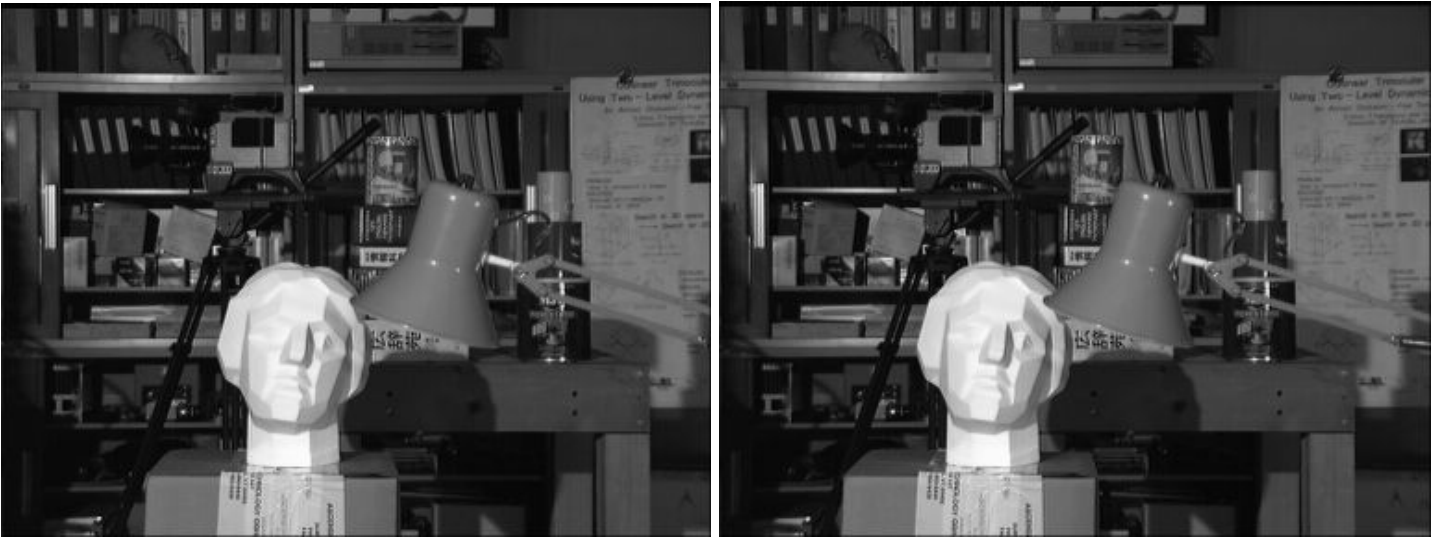


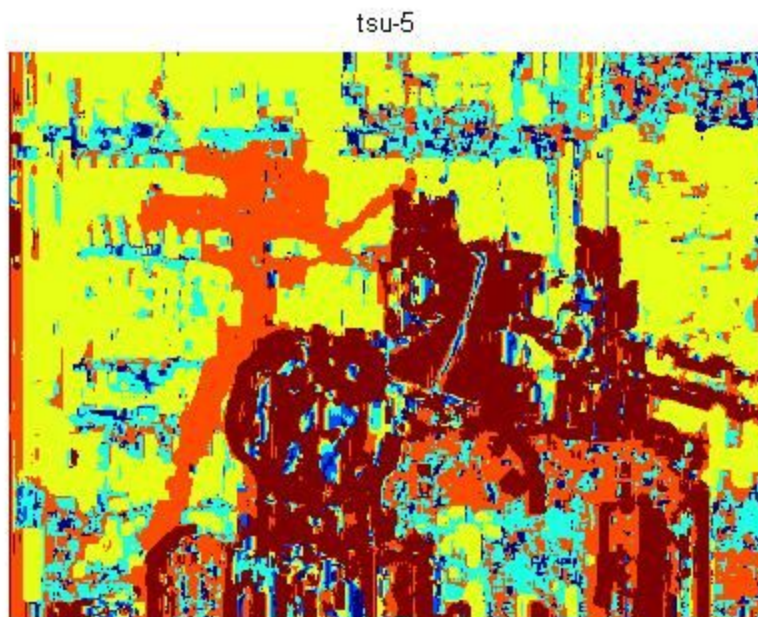
DISPARITY MAPPING

Original tsukuba stereo pair:



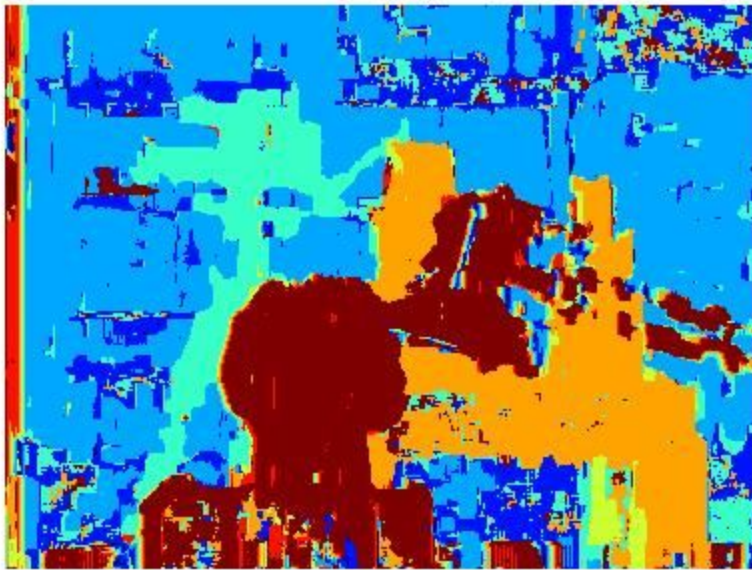
DISPARITY MAP COMPUTATION USING SSD:

With winsize= 5



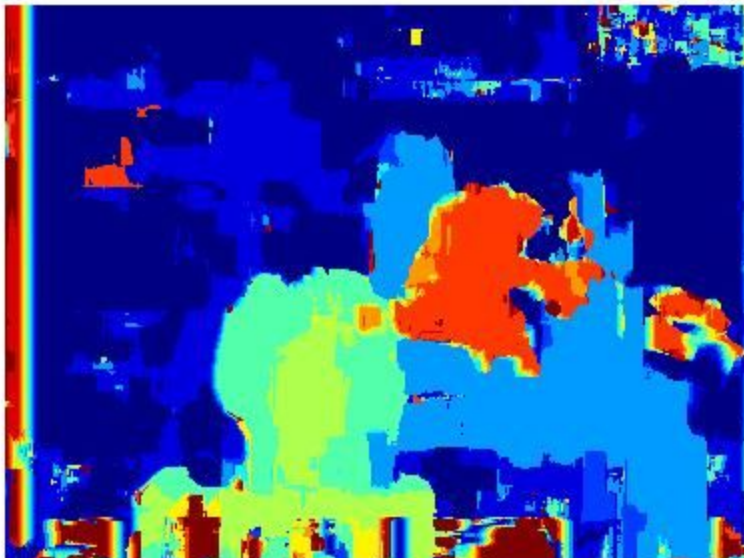
With winsize= 7

tsu-7



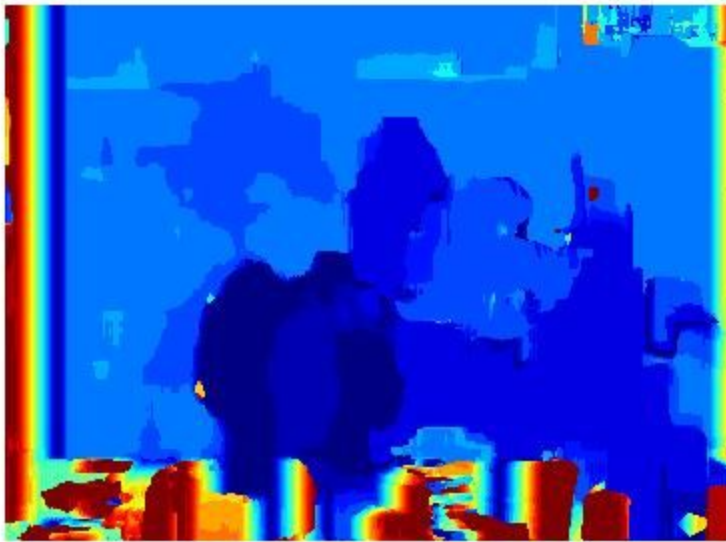
With winsize= 11

tsu-11



With winsize= 21

tsu-21



Smaller window (here 3x3) does compute disparity on finer scale but has a lot of noise. While Large window (here 21x21) smoothes the noise, edges information lost. A Medium sized(7x7 or 11x11) window is a trade off between the two and gives better results.

Also, the region in the right image in which we search for the disparity, the region should actually cover the disparity. Otherwise we may get false disparities and a bad disparity map.

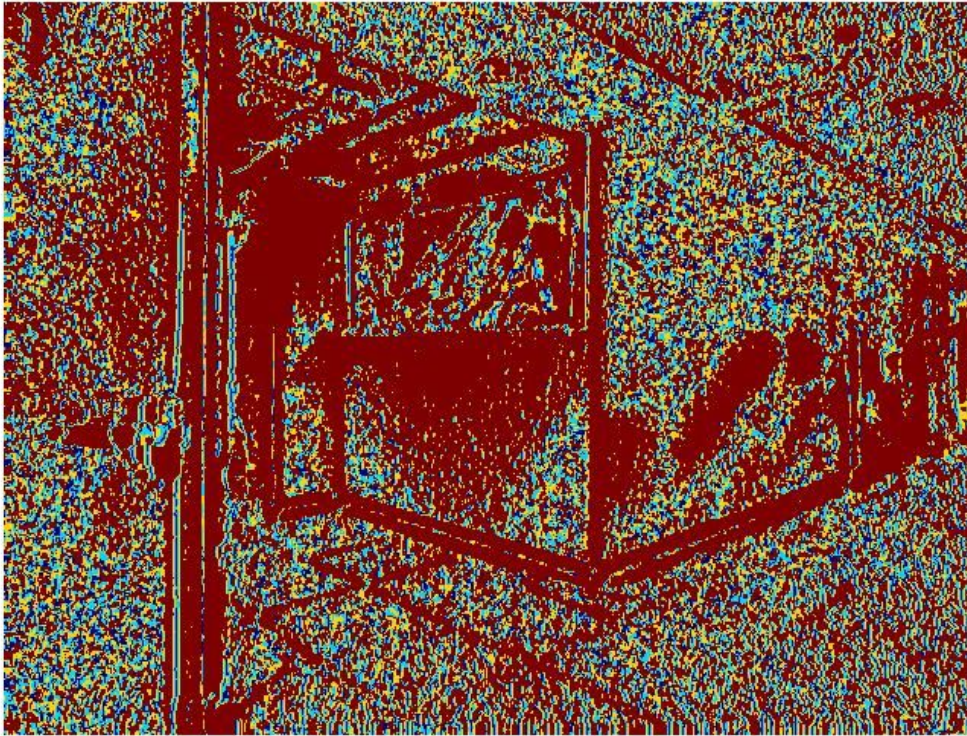
For 6567 pair, the consistency of the wall, makes it difficult to evaluate the disparity for the gradually farring off wall.

Original 6567 Stereo Pair:



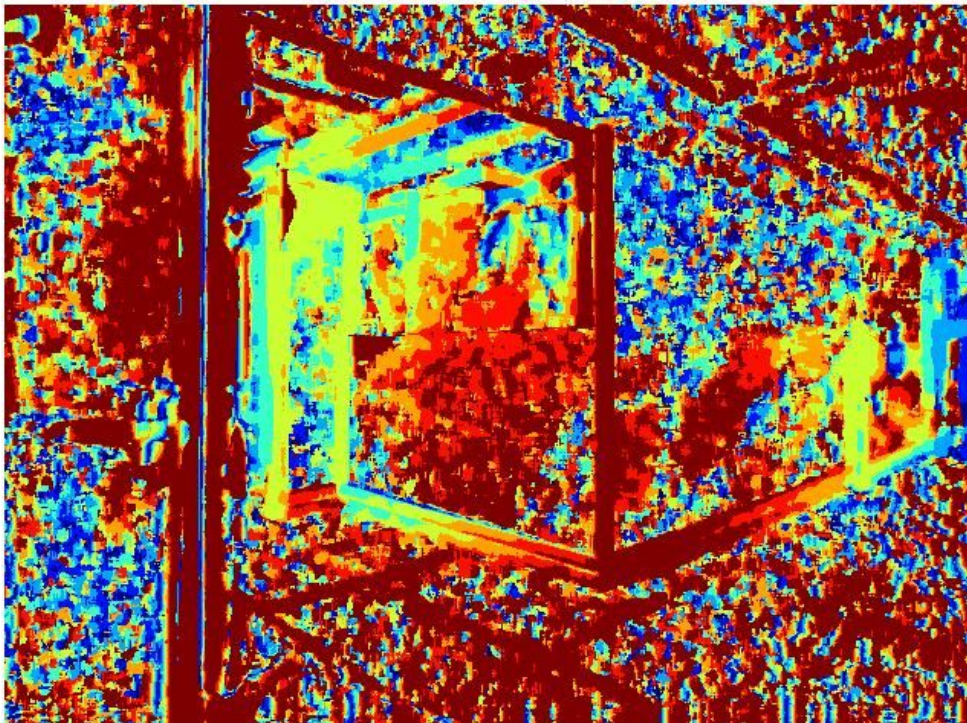
Disparity Map for 6567-Pair:
With winsize= 3

6567-3



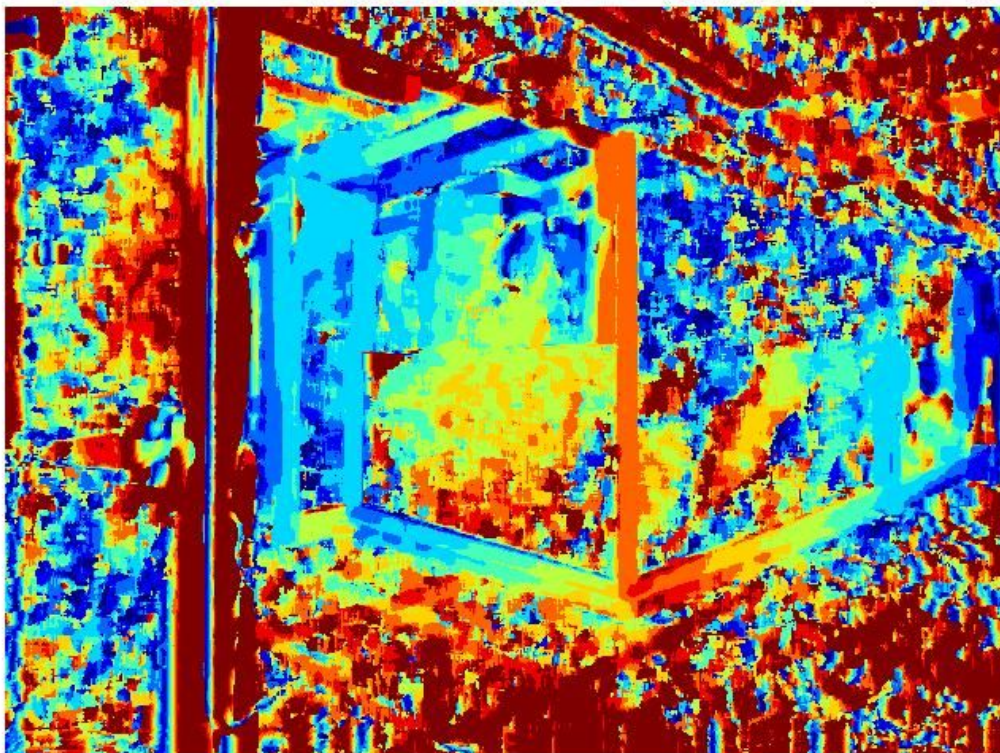
With winsize= 7

6567-7



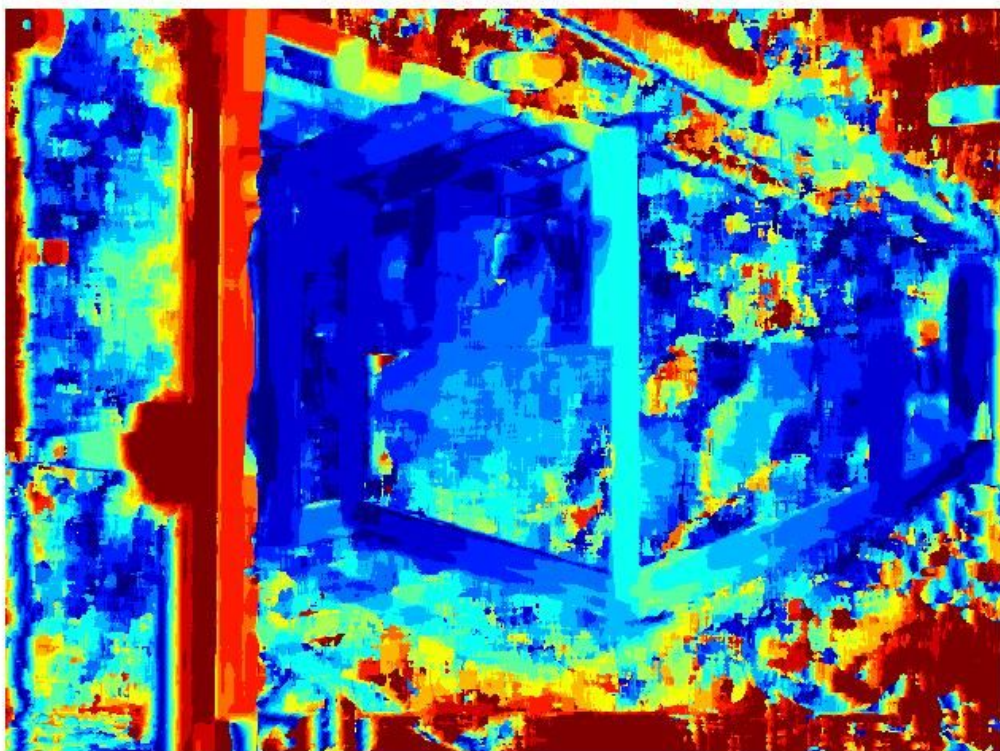
With winsize= 9

6567-9



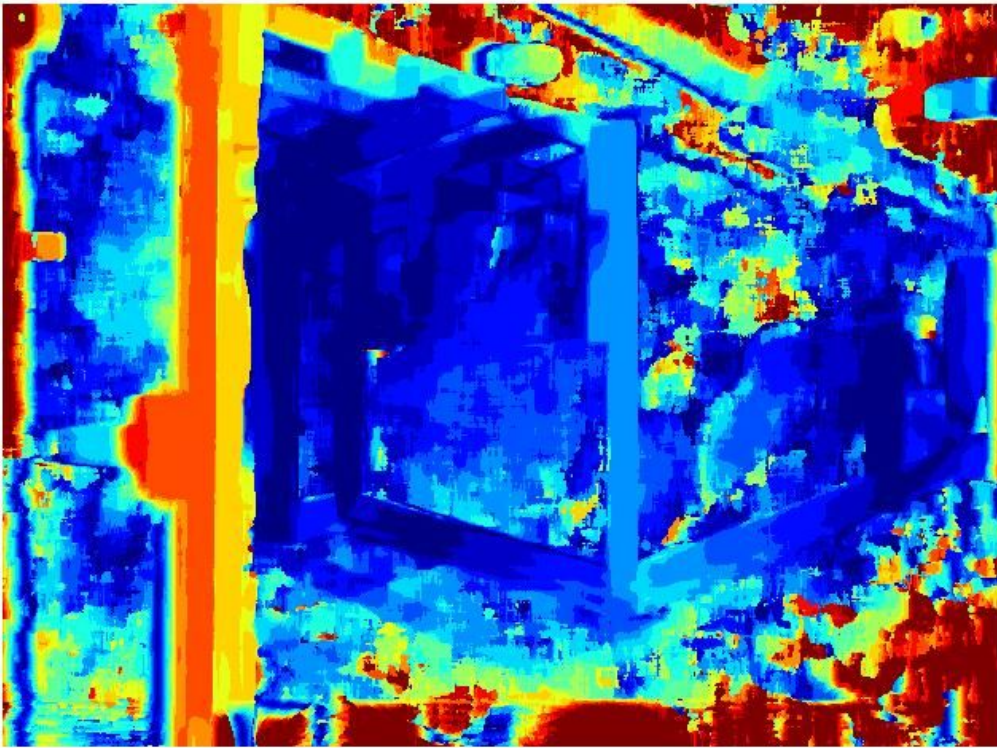
With winsize= 13

6567-13



With winsize= 15

6567-15



With winsize= 21

6567-21

