This folder contains a sample from the KITTI Stereo 2012 benchmark training set.

(http://www.cvlibs.net/datasets/kitti/eval\_stereo\_flow.php?benchmark=stereo)

Contents:

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- image\_0/1 : grayscale images from the left (image\_0) and right (image\_1) cameras.

- disp\_noc/occ : sparse ground truth disparity values acquired by accumulating 3D point clouds

from a 360 degree Velodyne HDL-64 Laserscanner. Here the suffix \_noc or \_occ

refers to whether the disparity is provided only for non-occluded pixels

(i.e., pixels visible to both cameras) or occluded pixels (i.e., all pixels).

The disparity images are aligned with the left camera.

- calib : text files containing 3x4 projection matrices for each of the four KITTI

cameras (P0 corresponds to image\_0, etc.).

- colored\_0/1 : RGB images from the from the left (image\_0) and right (image\_1) cameras.

File naming examples:

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Stereo pair '000010':

- left image : image\_0/000010\_10.png

- right image : image\_1/000010\_10.png

- ground truth disparity : disp\_noc/000010\_10.png

Data format:

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Disparity values range [0..255]. Disparity maps are saved as uint16 PNG images,

which can be opened with MATLAB, libpng++, or Pillow. A 0-value indicates that no ground

truth exists for that pixel. Otherwise the disparity for a pixel can be computed by

converting the uint16 value to float and dividing it by 256:

disp(u,v) = ((float)I(u,v))/256.0;

valid(u,v) = I(u,v)>0;