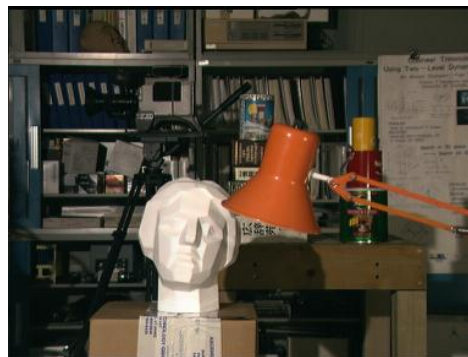


Dense Stereo Estimation

- For each pixel assigns a disparity label : z
- Disparities from the discrete set $\{0, 1, \dots, D\}$



Left Camera Image



Right Camera Image



Dense Stereo Result