

ABSTRACT

Embodiments of the present application disclose a binocular matching method, including: obtaining an image to be processed, where the image is a two-dimensional (2D) image including a left image and a right image; constructing a three-dimensional (3D) matching cost feature of the image by using extracted features of the left image and extracted features of the right image, where the 3D matching cost feature includes a group-wise cross-correlation feature, or includes a feature obtained by concatenating the group-wise cross-correlation feature and a connection feature; and determining the depth of the image by using the 3D matching cost feature. The embodiments of the present application also provide a binocular matching apparatus, a computer device, and a storage medium.

[Figure 1A]