

The purpose of this project is to propose and implement a system for object localization using a stereo vision – two cameras. The system computes the position of the cameras relatively to each other using a calibration pattern. Then a user selects an object to track. Different algorithms can be used for tracking. Both detection-based and sequence-based approaches can be used. When the object is found in the view of both cameras, the system estimates a position of the object in three-dimensional space using triangulation and displays the results live.