Conference and Workshop Papers

[C1] R. Maier, R. Schaller and D. Cremers,  
Efficient Online Surface Correction for Real-time Large-Scale 3D Reconstruction,  

[C2] R. Maier, J. Sturm and D. Cremers,  
Submap-based Bundle Adjustment for 3D Reconstruction from RGB-D Data,  
*German Conference on Pattern Recognition (GCPR)*, Münster, Germany, September 2014, Oral Presentation.

[C3] C. Kerl, J. Sturm and D. Cremers,  
Robust Odometry Estimation for RGB-D Cameras,  

[C4] E. Bylow, J. Sturm, C. Kerl, F. Kahl and D. Cremers,  
Real-Time Camera Tracking and 3D Reconstruction Using Signed Distance Functions,  

[C5] E. Bylow, J. Sturm, C. Kerl, F. Kahl and D. Cremers,  
Direct Camera Pose Tracking and Mapping With Signed Distance Functions,  
Demo Track of the RGB-D Workshop on Advanced Reasoning with Depth Cameras at the Robotics: Science and Systems Conference (RSS), June 2013.

[C6] C. Kerl, J. Sturm and D. Cremers,  
Dense Visual SLAM for RGB-D Cameras,  

[C7] J. Sturm, E. Bylow, F. Kahl and D. Cremers,  
Dense Tracking and Mapping with a Quadrocopter,  
*Unmanned Aerial Vehicle in Geomatics (UAV-g)*, Rostock, Germany, September 2013.

[C8] J. Sturm, E. Bylow, F. Kahl and D. Cremers,  
CopyMe3D: Scanning and Printing Persons in 3D,  
*German Conference on Pattern Recognition (GCPR)*, Saarbrücken, Germany, September 2013.

[C9] F. Endres, J. Hess, N. Engelhard, J. Sturm, D. Cremers and W. Burgard,  
An Evaluation of the RGB-D SLAM System,  

[C10] J. Sturm, N. Engelhard, F. Endres, W. Burgard and D. Cremers,  
A Benchmark for the Evaluation of RGB-D SLAM Systems,  

[C11] J. Sturm, W. Burgard and D. Cremers,  
Evaluating Egomotion and Structure-from-Motion Approaches Using the TUM RGB-D Benchmark,  
Keywords: Rgb-d Benchmark

List of Publications

[C12] N. Engelhard, F. Endres, J. Hess, J. Sturm and W. Burgard,
Real-time 3D visual SLAM with a hand-held camera,

Towards a benchmark for RGB-D SLAM evaluation,

[C14] F. Steinbruecker, J. Sturm and D. Cremers,
Real-Time Visual Odometry from Dense RGB-D Images,
Workshop on Live Dense Reconstruction with Moving Cameras at the Intl. Conf. on Computer Vision (ICCV), 2011.

MastersThesis

[M1] R. Maier,
Out-of-Core Bundle Adjustment for 3D Workpiece Reconstruction,
Technische Universität München, Germany, September 2013.

[M2] C. Kerl,
Odometry from RGB-D Cameras for Autonomous Quadrocopters,
Technical University Munich, Germany, Nov. 2012.