Conference and Workshop Papers

[C1] C. Kerl, J. Stueckler and D. Cremers, 
Dense Continuous-Time Tracking and Mapping with Rolling Shutter RGB-D Cameras,  
*IEEE International Conference on Computer Vision (ICCV)*, Santiago, Chile, 2015.

[C2] C. Kerl, J. Sturm and D. Cremers, 
Robust Odometry Estimation for RGB-D Cameras,  

[C3] C. Kerl, J. Sturm and D. Cremers, 
Dense Visual SLAM for RGB-D Cameras,  

[C4] 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.

Masters Thesis

[M1] C. Kerl, 
Odometry from RGB-D Cameras for Autonomous Quadrocopters,  
Technical University Munich, Germany, Nov. 2012.