Conference and Workshop Papers

[C1] M. Jaimez, C. Kerl, J. Gonzalez-Jimenez and D. Cremers,  
Fast Odometry and Scene Flow from RGB-D Cameras based on Geometric Clustering,  
Proc. of the IEEE Int. Conf. on Robotics and Automation (ICRA), 2017.

[C2] L. Ma, J. Stueckler, C. Kerl and D. Cremers,  
Multi-View Deep Learning for Consistent Semantic Mapping with RGB-D Cameras,  

[C3] L. Ma, C. Kerl, J. Stueckler and D. Cremers,  
CPA-SLAM: Consistent Plane-Model Alignment for Direct RGB-D SLAM,  
International Conference on Robotics and Automation (ICRA), May 2016.

[C4] 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.

[C5] C. Kerl, M. Souiai, J. Sturm and D. Cremers,  
Towards Illumination-invariant 3D Reconstruction using ToF RGB-D Cameras,  
International Conference on 3D Vision (3DV), 2014.

[C6] C. Kerl, J. Sturm and D. Cremers,  
Robust Odometry Estimation for RGB-D Cameras,  
International Conference on Robotics and Automation (ICRA), May 2013, Best Vision Paper Award - Finalist.

[C7] E. Bylow, J. Sturm, C. Kerl, F. Kahl and D. Cremers,  
Real-Time Camera Tracking and 3D Reconstruction Using Signed Distance Functions,  

[C8] 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.

[C9] C. Kerl, J. Sturm and D. Cremers,  
Dense Visual SLAM for RGB-D Cameras,  

[C10] F. Steinbruecker, C. Kerl, J. Sturm and D. Cremers,  
Large-Scale Multi-Resolution Surface Reconstruction from RGB-D Sequences,  
IEEE International Conference on Computer Vision (ICCV), Sydney, Australia, 2013.

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