Journal Articles


Conference and Workshop Papers


Author: Triebel

List of Publications

[C12] J Lee, M Hunt, J Feng and R Triebel,
Estimating Model Uncertainty of Neural Networks in Sparse Information Form,

[C13] J Liu, I Chiotellis, R Triebel and D Cremers,
Effective Version Space Reduction for Convolutional Neural Networks,
*European Conference on Machine Learning and Data Mining (ECML-PKDD)*, 2020.

[C14] M Denninger and R Triebel,
3D Scene Reconstruction from a Single Viewport,

[C15] M Sewtz, T Bodenmüller and R Triebel,
Robust MUSIC-Based Sound Source Localization in Reverberant and Echoic Environments,

[C16] CL Gentil, M Vayugundla, R Giubilato, W Stürzl, TA. Vidal-Calleja and R Triebel,
Gaussian Process Gradient Maps for Loop-Closure Detection in Unstructured Planetary Environments,

[C17] W Boerdijk, M Sundermeyer, M Durner and R Triebel,
Self-Supervised Object-in-Gripper Segmentation from Robotic Motions,
*Conference on Robot Learning (CoRL)*, 2020.

[C18] F Schiel, A Hagengruber, J Vogel and R Triebel,
Incremental learning of EMG-based control commands using Gaussian Processes,
*Conference on Robot Learning (CoRL)*, 2020.

[C19] M Stoiber, M Pfanne, K Strobl, R Triebel and A Albu-Schaeffer,
A Sparse Gaussian Approach to Region-Based 6DoF Object Tracking,
*Asian Conference on Computer Vision*, 2020, Best Paper Award.

[C20] L Meyer, K Strobl and R Triebel,
Robust Vision-Based Pose Correction for a Robotic Manipulator using Active Markers,

[C21] E.Y. Puang, P. Lehner, Z.C. Marton, M. Durner, R. Triebel and A. Albu-Schäffer,
Visual Repetition Sampling for Robot Manipulation Planning,

[C22] F. Steidle, W. Stürzl and R. Triebel,
Visual-inertial sensor fusion with a bio-inspired polarization compass for navigation of MAVs,

Introspective Robot Perception using Smoothed Predictions from Bayesian Neural Networks,
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Implicit 3D Orientation Learning for 6D Object Detection from RGB Images, 

[C26] M. Denninger and R. Triebel, 
Persistent Anytime Learning of Objects from Unseen Classes, 

[C27] I. Grixa, P. Schulz, W. Stürzl and R. Triebel, 
Appearance-Based Along-Route Localization for Planetary Missions, 

[C28] I. Chiotellis, F. Zimmermann, D. Cremers and R. Triebel, 
Incremental Semi-Supervised Learning from Streams for Object Classification, 

6DoF Pose Estimation for Industrial Manipulation based on Synthetic Data, 

[C30] C. Nissler, M. Durner, Z.-C. Marton and R. Triebel, 
Simultaneous Calibration and Mapping, 

[C31] M Ullrich, H Ali, M Durner, ZC Marton and R Triebel, 
Selecting CNN Features for Online Learning of 3D Objects, 

[C32] C Nissler, ZC Marton, H Kisner, U Thomas and R Triebel, 
A Method for Hand-Eye and Camera-to-Camera Calibration for Limited Fields of View, 

[C33] TS Wang, ZC Marton, M Brucker and R Triebel, 
How Robots Learn to Classify New Objects Trained from Small Data Sets, 
*Conference on Robot Learning (CoRL)*, 2017.

[C34] M Durner, S Kriegel, S Riedel, M Brucker, ZC Marton, F Balint-Benczedi and R Triebel, 
Experience-based Optimization of Robotic Perception, 
[C35] A. Narr, R. Triebel and D. Cremers,
Stream-based Active Learning for Efficient and Adaptive Classification of 3D Objects,

[C36] I. Chiotellis, R. Triebel, T. Windheuser and D. Cremers,
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Learning to Drive using Inverse Reinforcement Learning and Deep Q-Networks,
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[C38] D. Mund, R. Triebel and D. Cremers,
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V. Evers, M. Fiore, H. Hung, O. A. I Ramirez, M. Joosse, H. Kambhaita, T. Kucner, B.
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[C40] Y. Tao, R. Triebel and D. Cremers,
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[C41] F. Stark, C. Hazirbas, R. Triebel and D. Cremers,
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[C42] T. Windheuser, M. Vestner, E. Rodola, R. Triebel and D. Cremers,
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[C43] R. Triebel, J. Stühmer, M. Souiai and D. Cremers,
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[C47] R. Triebel, H. Grimmett and I. Posner,  
**Confidence Boosting: Improving the Introspectiveness of a Boosted Classifier for Efficient Learning,**  

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[C50] R. Paul, R. Triebel, D. Rus and P. Newman,  
**Semantic Categorization of Outdoor Scenes with Uncertainty Estimates using Multi-Class Gaussian Process Classification,**  

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[C52] J. Shin, R. Triebel and R. Siegwart,  
**Unsupervised 3D Object Discovery and Categorization for Mobile Robots,**  

[C53] J. Maye, R. Triebel, L. Spinello and R. Siegwart,  
**Bayesian On-line Learning of Driving Behaviors,**  

[C54] R. Kaestner, N. Engelhard, R. Triebel and R. Siegwart,  
**A Bayesian Approach to Learning 3D Representations of Dynamic Environments,**  

[C55] L. Spinello, R. Triebel, D. Vasquez, K. Arras and R Siegwart,  
**Exploiting Repetitive Object Patterns for Model Compression and Completion,**  
[C56] R. Triebel, J. Shin and R. Siegwart,
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[C57] L. Spinello, K. O. Arras, R. Triebel and R. Siegwart,
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[C60] L. Spinello, A. Macho, R. Triebel and R. Siegwart,
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[C61] L. Spinello, R. Triebel and R. Siegwart,
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with Explicit Ground Plane Extraction,

[C64] L. Spinello, R. Triebel and R. Siegwart,
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[C65] R. Triebel, O. M Mozos and W. Burgard,
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[C66] R. Kümerle, P. Pfaff, R. Triebel and W. Burgard,
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[C67] R. Triebel and W. Burgard,
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Multi-Level Surface Maps for Outdoor Terrain Mapping and Loop Closing,

[C71] R. Triebel, K. Kersting and W. Burgard,
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Using Hierarchical EM to Extract Planes from 3D Range Scans,

[C76] R. Triebel, B. Frank, J. Meyer and W. Burgard,
First steps towards a robotic system for flexible volumetric mapping of indoor environments,

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[C78] D. Hähnel, R. Triebel, W. Burgard and S. Thrun,
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