Journal Articles

[J1] T Yenamandra, A Tewari, N Yang, F Bernard, C Theobalt and D Cremers,  
HDSDF: Hybrid Directional and Signed Distance Functions for Fast Inverse Rendering,  
2022.

[J2] N. Yang, R. Wang, X. Gao and D. Cremers,  
Challenges in Monocular Visual Odometry: Photometric Calibration, Motion Bias and Rolling Shutter Effect,  

Conference and Workshop Papers

[C1] F. Wimbauer, N. Yang, L. von Stumberg, N. Zeller and D. Cremers,  
MonoRec: Semi-Supervised Dense Reconstruction in Dynamic Environments from a Single Moving Camera,  

[C2] L Koestler, N Yang, N Zeller and D Cremers,  
TANDEM: Tracking and Dense Mapping in Real-time using Deep Multi-view Stereo,  
Conference on Robot Learning (CoRL), 2021, 3DV’21 Best Demo Award.

[C3] R. Wang, N. Yang, J. Stueckler and D. Cremers,  
DirectShape: Photometric Alignment of Shape Priors for Visual Vehicle Pose and Shape Estimation,  

[C4] N. Yang, L. von Stumberg, R. Wang and D. Cremers,  
D3VO: Deep Depth, Deep Pose and Deep Uncertainty for Monocular Visual Odometry,  

[C5] L. Koestler, N. Yang, R. Wang and D. Cremers,  
Learning Monocular 3D Vehicle Detection without 3D Bounding Box Labels,  

4Seasons: A Cross-Season Dataset for Multi-Weather SLAM in Autonomous Driving,  

[C7] L. von Stumberg, P. Wenzel, N. Yang and D. Cremers,  
LM-Reloc: Levenberg-Marquardt Based Direct Visual Relocalization,  
[C8] E. Jung, N. Yang and D. Cremers,
Multi-Frame GAN: Image Enhancement for Stereo Visual Odometry in Low Light,
Conference on Robot Learning (CoRL), 2019, Full Oral Presentation.

[C9] N. Yang, R. Wang, J. Stueckler and D. Cremers,
Deep Virtual Stereo Odometry: Leveraging Deep Depth Prediction for Monocular Direct Sparse Odometry,
European Conference on Computer Vision (ECCV), September 2018, Oral Presentation.