Keywords: Slam

List of Publications

2022
Journal Articles

[J1] L. von Stumberg and D. Cremers,
DM-VIO: Delayed Marginalization Visual-Inertial Odometry,

Conference and Workshop Papers

[C1] D Muhle, L Koestler, N Demmel, F Bernard and D Cremers,
The Probabilistic Normal Epipolar Constraint for Frame-To-Frame Rotation Optimization under Uncertain Feature Positions,
*IEEE Conference on Computer Vision and Pattern Recognition (CVPR)*, 2022.

[C2] S Weber, N Demmel, T Chon Chan and D Cremers,
Power Bundle Adjustment for Large-Scale 3D Reconstruction,
*submission*, 2022.

[C3] M Gladkova, N Korobov, N Demmel, A Osep, L Leal-Taixe and D Cremers,
DirectTracker: 3D Multi-Object Tracking Using Direct Image Alignment and Photometric Bundle Adjustment,

2021
Journal Articles

[J1] J. Chui, S. Klenk and D. Cremers,
Event-Based Feature Tracking in Continuous Time with Sliding Window Optimization,

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,
*IEEE Conference on Computer Vision and Pattern Recognition (CVPR)*, 2021.

[C2] M Gladkova, R Wang, N Zeller and D Cremers,
Tight Integration of Feature-based Relocalization in Monocular Direct Visual Odometry,

[C3] Y. Xia, Y. Xu, S. Li, R. Wang, J. Du, D. Cremers and U. Stilla,
SOE-Net: A Self-Attention and Orientation Encoding Network for Point Cloud based Place Recognition,
*IEEE Conference on Computer Vision and Pattern Recognition (CVPR)*, 2021, *Oral Presentation*. 
[C4] N Demmel, C Sommer, D Cremers and V Usenko, 
Square Root Bundle Adjustment for Large-Scale Reconstruction,

[C5] N Demmel, D Schubert, C Sommer, D Cremers and V Usenko, 
Square Root Marginalization for Sliding-Window Bundle Adjustment,
IEEE International Conference on Computer Vision (ICCV), 2021.

[C6] MW Wudenka, MG Müller, N Demmel, A Wedler, R Triebel, D Cremers and W Stuerzl, 
Towards Robust Monocular Visual Odometry for Flying Robots on Planetary Missions,

[C7] S Klenk, J Chui, N Demmel and D Cremers, 
TUM-VIE: The TUM Stereo Visual-Inertial Event Dataset,

[C8] 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.

[C9] S Weber, N Demmel and D Cremers, 
Multidirectional Conjugate Gradients for Scalable Bundle Adjustment,
German Conference on Pattern Recognition (GCPR), 2021, Oral Presentation.

2020

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[J1] V. Usenko, N. Demmel, D. Schubert, J. Stueckler and D. Cremers, 
Visual-Inertial Mapping with Non-Linear Factor Recovery,

[J2] L. von Stumberg, P. Wenzel, Q. Khan and D. Cremers, 
GN-Net: The Gauss-Newton Loss for Multi-Weather Relocalization,

Conference and Workshop Papers

[C1] R. Wang, N. Yang, J. Stueckler and D. Cremers, 
DirectShape: Photometric Alignment of Shape Priors for Visual Vehicle Pose and Shape Estimation,

[C2] C. Sommer, V. Usenko, D. Schubert, N. Demmel and D. Cremers, 
Efficient Derivative Computation for Cumulative B-Splines on Lie Groups,

[C3] N. Yang, L. von Stumberg, R. Wang and D. Cremers, 
D3VO: Deep Depth, Deep Pose and Deep Uncertainty for Monocular Visual Odometry,
Keywords: Slam

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[C4] J. Du, R. Wang and D. Cremers,
DH3D: Deep Hierarchical 3D Descriptors for Robust Large-Scale 6DoF Relocalization,
European Conference on Computer Vision (ECCV), 2020, Spotlight Presentation.

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

[C6] N. Demmel, M. Gao, E. Laude, T. Wu and D. Cremers,
Distributed Photometric Bundle Adjustment,

[C7] L. von Stumberg, P. Wenzel, N. Yang and D. Cremers,
LM-Reloc: Levenberg-Marquardt Based Direct Visual Relocalization,

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Conference and Workshop Papers

[C1] D. Schubert, N. Demmel, L. von Stumberg, V. Usenko and D. Cremers,
Rolling-Shutter Modelling for Visual-Inertial Odometry,

[C2] F. Steidle, W. Stürzl and R. Triebel,
Visual-inertial sensor fusion with a bio-inspired polarization compass for navigation of MAVs,
11th International Micro Air Vehicle Competition and Conference (IMAV), 2019.

2018
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[J1] J. Engel, V. Koltun and D. Cremers,
Direct Sparse Odometry,

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

[J3] P. Bergmann, R. Wang and D. Cremers,
Online Photometric Calibration of Auto Exposure Video for Realtime Visual Odometry and SLAM,

Omnidirectional DSO: Direct Sparse Odometry with Fisheye Cameras,
Conference and Workshop Papers

[C1] C. Sommer and D. Cremers,

[C2] R Scona, M Jaimez, YR. Petillot, M Fallon and D Cremers,
StaticFusion: Background Reconstruction for Dense RGB-D SLAM in Dynamic Environments,

[C3] L. von Stumberg, V. Usenko and D. Cremers,


[C5] X. Gao, R. Wang, N. Demmel and D. Cremers,

[C6] N. Yang, R. Wang, J. Stueckler and D. Cremers,

[C7] D. Schubert, N. Demmel, V. Usenko, J. Stueckler and D. Cremers,

[C8] V. Usenko, N. Demmel and D. Cremers,

2017
Conference and Workshop Papers

[C1] G. Kuschk, A. Bozic and D. Cremers,

[C2] M. Dzitsiuk, J. Sturm, R. Maier, L. Ma and D. Cremers,
Keywords: Slam

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[C3] L. von Stumberg, V. Usenko, J. Engel, J. Stueckler and D. Cremers,
From Monocular SLAM to Autonomous Drone Exploration,
European Conference on Mobile Robots (ECMR), September 2017.

[C4] R. Maier, R. Schaller and D. Cremers,
Efficient Online Surface Correction for Real-time Large-Scale 3D Reconstruction,
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[C5] A. Kasyanov, F. Engelmann, J. Stueckler and B. Leibe,
Keyframe-Based Visual-Inertial Online SLAM with Relocalization,

2016
Conference and Workshop Papers

[C1] V. Usenko, J. Engel, J. Stueckler and D. Cremers,
Direct Visual-Inertial Odometry with Stereo Cameras,
International Conference on Robotics and Automation (ICRA), May 2016.

[C2] 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.

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A Photometrically Calibrated Benchmark For Monocular Visual Odometry,

[C4] J. Engel, V. Koltun and D. Cremers,
Direct Sparse Odometry,

[C5] D. Bender, F. Rouatbi, M. Schikora, D. Cremers and W. Koch,
Scaling the world of monocular SLAM with INS-measurements for UAS navigation,

2015
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Fast Visual Odometry for 3-D Range Sensors,

[J2] D. Droeschel, M. Nieuwenhuisen, M. Beul, J. Stueckler, D. Holz and S. Behnke,
Multi-Layered Mapping and Navigation for Autonomous Micro Aerial Vehicles,

Conference and Workshop Papers

[C1] J. Engel, J. Stueckler and D. Cremers,
Large-Scale Direct SLAM with Stereo Cameras,
Keywords: Slam

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[C2] D. Caruso, J. Engel and D. Cremers,
Large-Scale Direct SLAM for Omnidirectional Cameras,

[C3] V. Usenko, J. Engel, J. Stueckler and D. Cremers,
Reconstructing Street-Scenes in Real-Time From a Driving Car,

[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.

2014

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[J1] J. Engel, J. Sturm and D. Cremers,
Scale-Aware Navigation of a Low-Cost Quadrocopter with a Monocular Camera,

[J2] J. Stueckler and S. Behnke,
Multi-Resolution Surfel Maps for Efficient Dense 3D Modeling and Tracking,

Conference and Workshop Papers

[C1] D. B. AD. CJ. C D. Weikersdorfer,
Event-based 3D SLAM with a depth-augmented dynamic vision sensor,

[C2] F. Steinbruecker, J. Sturm and D. Cremers,
Volumetric 3D Mapping in Real-Time on a CPU,

[C3] H. Alvarez, L.M. Paz, J. Sturm and D. Cremers,
Collision Avoidance for Quadrotors with a Monocular Camera,

[C4] J. Engel, T. Schöps and D. Cremers,
LSD-SLAM: Large-Scale Direct Monocular SLAM,
*European Conference on Computer Vision (ECCV)*, September 2014, Oral Presentation.

[C5] T. Schöps, J. Engel and D. Cremers,
Semi-Dense Visual Odometry for AR on a Smartphone,

[C6] 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.
Keywords: Slam

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[C7] O. Dunkley, J. Engel, J. Sturm and D. Cremers,
Visual-Inertial Navigation for a Camera-Equipped 25g Nano-Quadrotor,

[C8] D. Droeschel, J. Stueckler and S. Behnke,
Local Multi-Resolution Surfel Grids for MAV Motion Estimation and 3D Mapping,

[C9] J. Stueckler, A. Gutt and S. Behnke,
Combining the Strengths of Sparse Interest Point and Dense Image Registration for RGB-D Odometry,
Proc. of the Joint 45th International Symposium on Robotics (ISR) and 8th German Conference on Robotics (ROBOTIK), to appear, jun 2014.

[C10] D. Droeschel, J. Stueckler and S. Behnke,
Local multi-resolution representation for 6D motion estimation and mapping with a continuously rotating 3D laser scanner,
Proc. of the IEEE Int. Conf. on Robotics and Automation (ICRA), 5221-5226, may 2014.

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[M1] T Schöps,
Semi-dense visual SLAM on mobile devices,
Technical University Munich, Germany, May 2014.

[M2] M. Shelley,
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Technical University Munich, Germany, Aug. 2014.

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Technical University Munich, Germany, Sept. 2014.

2013

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[J1] F. Endres, J. Hess, J. Sturm, D. Cremers and W. Burgard,
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[C1] C. Kerl, J. Sturm and D. Cremers,
Robust Odometry Estimation for RGB-D Cameras,
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[C2] E. Bylow, J. Sturm, C. Kerl, F. Kahl and D. Cremers,
Real-Time Camera Tracking and 3D Reconstruction Using Signed Distance Functions,
Keywords: Slam

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[C3] 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

[C4] C. Kerl, J. Sturm and D. Cremers,
Dense Visual SLAM for RGB-D Cameras,

[C5] 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.

[C6] J. Engel, J. Sturm and D. Cremers,
Semi-Dense Visual Odometry for a Monocular Camera,
IEEE International Conference on Computer Vision (ICCV), Sydney, Australia, December 2013.

[C7] 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.

[C8] M. Schadler, J. Stueckler and S. Behnke,
Multi-resolution surfel mapping and real-time pose tracking using a continuously rotating 2D laser scanner,

[C9] M. McElhone, J. Stueckler and S. Behnke,
Joint detection and pose tracking of multi-resolution surfel models in RGB-D,

[C10] J. Stueckler and S. Behnke,
Hierarchical Object Discovery and Dense Modelling From Motion Cues in
RGB-D Video,

MastersThesis

[M1] R. Maier,
Out-of-Core Bundle Adjustment for 3D Workpiece Reconstruction,
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2012
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[C1] F. Endres, J. Hess, N. Engelhard, J. Sturm, D. Cremers and W. Burgard,
An Evaluation of the RGB-D SLAM System,

[C2] J. Engel, J. Sturm and D. Cremers,
Camera-Based Navigation of a Low-Cost Quadrocopter,
Keywords: Slam

List of Publications

[C3]  J. Sturm, N. Engelhard, F. Endres, W. Burgard and D. Cremers,
     A Benchmark for the Evaluation of RGB-D SLAM Systems,

[C4]  J. Engel, J. Sturm and D. Cremers,
     Accurate Figure Flying with a Quadrocopter Using Onboard Visual and Inertial Sensing,

[C5]  J. Sturm, W. Burgard and D. Cremers,
     Evaluating Egomotion and Structure-from-Motion Approaches Using the TUM RGB-D Benchmark,

[C6]  J. Stueckler and S. Behnke,
     Integrating depth and color cues for dense multi-resolution scene mapping using RGB-D cameras,
     Proc. of the IEEE Int. Conf. on Multisensor Fusion and Integration for Intelligent Systems (MFI), 162-167, sep 2012.

[C7]  J. Stueckler and S. Behnke,
     Robust Real-Time Registration of RGB-D Images using Multi-Resolution Surfel Representations,

MastersThesis

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

2011

Conference and Workshop Papers

[C1]  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,

[C3]  F. Steinbruecker, J. Sturm and D. Cremers,
     Real-Time Visual Odometry from Dense RGB-D Images,
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Technical University Munich, Germany, Dec. 2011, Distinguished with the SIEMENS award for best Master’s Thesis 2012.

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[C3] M. Nieuwenhuisen, J. Stueckler and S. Behnke,
Improving indoor navigation of autonomous robots by an explicit representation of doors,
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