

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,
Vancouver, Canada, Sep 2017.
- [C3] L. Ma, C. Kerl, J. Stueckler and D. Cremers,
CPA-SLAM: Consistent Plane-Model Alignment for Direct RGB-D SLAM,
May 2016.
- [C4] C. Kerl, J. Stueckler and D. Cremers,
Dense Continuous-Time Tracking and Mapping with Rolling Shutter RGB-D Cameras,
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,
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,
Robotics: Science and Systems Conference (RSS), June 2013.
- [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,
Proc. of the Int. Conf. on Intelligent Robot Systems (IROS), 2013.
- [C10] F. Steinbruecker, C. Kerl, J. Sturm and D. Cremers,
Large-Scale Multi-Resolution Surface Reconstruction from RGB-D Sequences,
Sydney, Australia, 2013.

MastersThesis

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