2021

2020

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[J1] U Bonde, PF Alcantarilla and S Leutenegger,
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[J2] D Tzoumanikas, F Graule, Q Yan, D Shah, M Popovic and S Leutenegger,
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[J3] S Leutenegger,
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[J4] B Xu, AJ Davison and S Leutenegger,
Deep Probabilistic Feature-metric Tracking,

[J5] N Funk, J Tarrio, S Papatheodorou, M Popovic, PF Alcantarilla and S Leutenegger,
Multi-resolution 3D mapping with explicit free space representation for fast and accurate mobile robot motion planning,

[J6] Y Wang, N Funk, M Ramezani, S Papatheodorou, M Popovic, M Camurri, S Leutenegger and M Fallon,
Elastic and Efficient LiDAR Reconstruction for Large-Scale Exploration Tasks,

[J7] M Popovic, F Thomas, S Papatheodorou, N Funk, T Vidal-Calleja and S Leutenegger,
Efficient Volumetric Mapping Using Depth Completion With Uncertainty for Robotic Navigation,

Conference and Workshop Papers

[C1] A Dai, S Papatheodorou, N Funk, D Tzoumanikas and S Leutenegger,
Fast frontier-based information-driven autonomous exploration with an MAV,

[C2] D Tzoumanikas, Q Yan and S Leutenegger,
Nonlinear mpc with motor failure identification and recovery for safe and aggressive multicopter flight,

[C3] Z Landgraf, F Falck, M Bloesch, S Leutenegger and AJ Davison,
Comparing view-based and map-based semantic labelling in real-time SLAM,
[C4] T Laidlow, J Czarnowski, A Nicastro, R Clark and S Leutenegger,
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[C5] J Ortiz, M Pupilli, S Leutenegger and AJ Davison,
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[J2] K Zhang, P Chermprayong, D Tzoumanikas, W Li, M Grimm, M Smentoch, S Leutenegger and M Kovac,
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[J3] G Gallego, T Delbruck, G Orchard, C Bartolozzi, B Taba, A Censi, S Leutenegger, A Davison, J Conradt, K Daniilidis and others,
Event-based vision: A survey,

[J4] TK Kim, S Zafeiriou, B Glocker and S Leutenegger,
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[C2] A Nicastro, R Clark and S Leutenegger,
X-section: Cross-section prediction for enhanced RGB-D fusion,

[C3] S Zhi, M Bloesch, S Leutenegger and AJ Davison,
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KO-Fusion: dense visual SLAM with tightly-coupled kinematic and odometric tracking,
[C5] T Laidlow, J Czarnowski and S Leutenegger,
DeepFusion: real-time dense 3D reconstruction for monocular SLAM using single-view depth and gradient predictions,

[C6] S Saeedi, ED Carvalho, W Li, D Tzoumanikas, S Leutenegger, PH Kelly and AJ Davison,
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[C7] M Bloesch, T Laidlow, R Clark, S Leutenegger and AJ Davison,
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[C8] E Vespa, N Funk, PH Kelly and S Leutenegger,
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[J3] W Li, S Saeedi, J McCormac, R Clark, D Tzoumanikas, Q Ye, Y Huang, R Tang and S Leutenegger,
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Ls-net: Learning to solve nonlinear least squares for monocular stereo,

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[C1] M Bloesch, J Czarnowski, R Clark, S Leutenegger and AJ Davison,
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[J1] P Oettershagen, A Melzer, T Mantel, K Rudin, T Stastny, B Wawrzacz, T Hinzmann, S Leutenegger, K Alexis and R Siegwart,
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[C2] R Lukierski, S Leutenegger and AJ Davison,
Room layout estimation from rapid omnidirectional exploration,

[C3] L Platinsky, AJ Davison and S Leutenegger,
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[C4] J Czarnowski, S Leutenegger and AJ Davison,
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[J2] T Whelan, RF Salas-Moreno, B Glocker, AJ Davison and S Leutenegger,
ElasticFusion: Real-time dense SLAM and light source estimation,

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[BC1] S Leutenegger, C Hürzeler, AK Stowers, K Alexis, MW Achtelik, D Lentink, PY Oh and R Siegwart,
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[C1] E Johns, S Leutenegger and AJ Davison,
Pairwise decomposition of image sequences for active multi-view recognition,

[C2] P Bardow, AJ Davison and S Leutenegger,
Simultaneous optical flow and intensity estimation from an event camera,

[C3] E Johns, S Leutenegger and AJ Davison,
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[C4] J Zienkiewicz, A Davison and S Leutenegger,
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[C5] H Kim, S Leutenegger and AJ Davison,
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[J2] M Milford, H Kim, M Mangan, S Leutenegger, T Stone, B Webb and A Davison,
Place recognition with event-based cameras and a neural implementation of SeqSLAM,

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[C1] P Oettershagen, A Melzer, T Mantel, K Rudin, R Lotz, D Siebenmann, S Leutenegger, K Alexis and R Siegwart, 
A solar-powered hand-launchable UAV for low-altitude multi-day continuous flight, 

[C2] M Milford, H Kim, S Leutenegger and A Davison, 
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The problem of mobile sensors workshop in conjunction with RSS, 2015.

[C3] R Lukierski, S Leutenegger and AJ Davison, 
Rapid free-space mapping from a single omnidirectional camera, 

[C4] T Whelan, S Leutenegger, RF. Salas-Moreno, B Glocker and AJ. Davison, 
ElasticFusion: Dense SLAM Without A Pose Graph, 

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[C1] J Nikolic, J Rehder, M Burri, P Gohl, S Leutenegger, PT Furgale and R Siegwart, 
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Explicit model predictive control and l 1-navigation strategies for fixed-wing uav path tracking, 
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[C3] S Leutenegger, A Melzer, K Alexis and R Siegwart, 
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[J1] M Bloesch, M Hutter, MA Hoepflinger, S Leutenegger, C Gehring, CD Remy and R Siegwart, 
State estimation for legged robots-consistent fusion of leg kinematics and IMU, 

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[C1] J Nikolic, M Burri, J Rehder, S Leutenegger, C Huerzeler and R Siegwart, 
A UAV system for inspection of industrial facilities, 

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[C3] L Marconi, S Leutenegger, S Lynen, M Burri, R Naldi and C Melchiorri, 
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[C1] S Leutenegger, M Chli and RY Siegwart, 
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[C2] P Fankhauser, S Bouabdallah, S Leutenegger and R Siegwart, 
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    *Modeling and control of a ballbot*,
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2009
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[J1] A Noth,
    *Designing solar airplanes for continuous flight*,

2008
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[C1] C Bermes, S Leutenegger, S Bouabdallah, D Schafroth and R Siegwart,
    *New design of the steering mechanism for a mini coaxial helicopter*,

[C2] C Bermes, S Leutenegger, S Bouabdallah and R Siegwart,
    *Design and Comparison of a Steering Mechanism for an Autonomous Coaxial Indoor Helicopter*,

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    *Mechanical design and realization of a steering mechanism for a coaxial helicopter*,

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[C1] DJ Bell, S Leutenegger, K Hammar, L Dong and BJ Nelson,
    *Flagella-like propulsion for microrobots using a nanocoil and a rotating electromagnetic field*,