Stanford

Jeannette Bohg

Associate Professor of Computer Science

Bio

BIO

Jeannette Bohg is an Assistant Professor of Computer Science at Stanford University. She was a group leader at the Autonomous Motion Department (AMD) of the MPI for Intelligent Systems until September 2017. Before joining AMD in January 2012, Jeannette Bohg was a PhD student at the Division of Robotics, Perception and Learning (RPL) at KTH in Stockholm. In her thesis, she proposed novel methods towards multi-modal scene understanding for robotic grasping. She also studied at Chalmers in Gothenburg and at the Technical University in Dresden where she received her Master in Art and Technology and her Diploma in Computer Science, respectively. Her research focuses on perception and learning for autonomous robotic manipulation and grasping. She is specifically interesting in developing methods that are goal-directed, real-time and multi-modal such that they can provide meaningful feedback for execution and learning. Jeannette Bohg has received several awards, most notably the 2019 IEEE International Conference on Robotics and Automation (ICRA) Best Paper Award, the 2019 IEEE Robotics and Automation Society Early Career Award and the 2017 IEEE Robotics and Automation Letters (RA-L) Best Paper Award.

ACADEMIC APPOINTMENTS

- Associate Professor, Computer Science
- Member, Bio-X
- Faculty Affiliate, Institute for Human-Centered Artificial Intelligence (HAI)

HONORS AND AWARDS

- Research Award, Okawa Foundation (2019)
- Research Award, Amazon (2019)
- Early Academic Career Award in Robotics and Automation, Robotics and Automation Society (2019)
- Early Career Award, Robotics: Science and Systems (2020)
- Research Fellowship, Alfred P. Sloan Foundation (2023)

PROGRAM AFFILIATIONS

- Stanford SystemX Alliance

LINKS

- Personal Page: https://web.stanford.edu/~bohg/
- Interactive Perception and Robot Learning lab: iprl.stanford.edu

Teaching

COURSES

2025-26

- Fundamentals of Visual Perspective and its Influence on Renaissance Art, AI and Robotics: OSPFLOR 60F (Aut)

2024-25

- Computer Vision: From 3D Perception to 3D Reconstruction and Beyond: CS 231A (Spr)
- Principles of Robot Autonomy I: AA 274A, CS 237A, EE 260A, ME 274A (Aut)
- Principles of Robot Autonomy II: AA 174B, AA 274B, CS 237B, EE 260B, ME 274B (Win)
- Topics in Advanced Robotic Manipulation: CS 326 (Aut)

2023-24

- Computer Vision: From 3D Perception to 3D Reconstruction and Beyond: CS 231A (Spr)
- Principles of Robot Autonomy II: AA 174B, AA 274B, CS 237B (Win)
- Topics in Advanced Robotic Manipulation: CS 326 (Aut)

STANFORD ADVISEES

Doctoral Dissertation Reader (AC)

William Chong, Yunfan Jiang, Zeyi Liu, Gadi Sznaier Camps, Xiaomeng Xu, Mandi Zhao

Postdoctoral Faculty Sponsor

Cherie Ho, Alberta Longhini

Doctoral Dissertation Advisor (AC)

Jingyun Yang

Doctoral Dissertation Co-Advisor (AC)

Erik Bauer, Suning Huang, Tyler Lum, Juntao Ren, Matt Strong

Master's Program Advisor

Aditi Bhaskar, Ayaan Chand, Andrew Chen, Miriam Min-Chen Cheng, Michael Jang, Romina Jately, Feiyang Kuang, Annika Singh, Olivia Taylor

Doctoral (Program)

Ria Doshi, Carlota Pares Morlans, Satvik Sharma, Lei Shu, Jingyun Yang

Publications

PUBLICATIONS

- **Gentle Object Retraction in Dense Clutter Using Multimodal Force Sensing and Imitation Learning** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Brouwer, D., Citron, J., Nolte, H., Bohg, J., Cutkosky, M.
  2026; 11 (2): 1578-1585
- **SLAG: Scalable Language-Augmented Gaussian Splatting** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Szilagyi, L., Engelmann, F., Bohg, J.
  2025; 10 (7): 6991-6998
- **DexForce: Extracting Force-Informed Actions From Kinesthetic Demonstrations for Dexterous Manipulation** *IEEE ROBOTICS AND AUTOMATION LETTERS*

Chen, C., Yu, Z., Choi, H., Cutkosky, M., Bohg, J.
2025; 10 (6): 6416-6423

- **ACGD: Visual Multitask Policy Learning with Asymmetric Critic Guided Distillation**
  Srinivasan, K., Xu, J., Ang, H., Heiden, E., Fox, D., Bohg, J., Garg, A.
  edited by Laugier, C., Atanasov, N., Birchfield, S., Cielniak, G., DeMattos, L., Fiorini, L., Giguere, P., Hashimoto, K., Ibanez-Guzman, J., Kamegawa, T., Lee, J., Laugier, C., Loianno, G., Luck, K., Maruyama, H., Martinet, P., Moradi, H., Nunes, U., Pettre, J., Pretto, A., Ranzani, T., Ronnau, A., Rossi, S., Rouse, E., Ruggiero, F., Simonin, O., Wang, D., Yang, M., Yoshida, E., Zhao, H.
  IEEE.2025: 583-590

- **Phantom: Training Robots Without Robots Using Only Human Videos**
  Lepert, M., Fang, J., Bohg, J.
  edited by Lim, J., Song, S., Park, H. W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2025: 4545-4565

- **Vision in Action: Learning Active Perception from Human Demonstrations**
  Xiong, H., Xu, X., Wu, J., Hou, Y., Bohg, J., Song, S.
  edited by Lim, J., Song, S., Park, H. W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2025: 5450-5463

- **Mobi-π: Mobilizing Your Robot Learning Policy**
  Yang, J., Huang, I., Vu, B., Bajracharya, M., Antonova, R., Bohg, J.
  edited by Lim, J., Song, S., Park, H. W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2025: 3516-3536

- **CUPID: Curating Data your Robot Loves with Influence Functions**
  Agia, C., Sinha, R., Yang, J., Antonova, R., Payone, M., Nishimura, H., Itkina, M., Bohg, J.
  edited by Lim, J., Song, S., Park, H. W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2025: 2907-2932

- **Constraint-Preserving Data Generation for Visuomotor Policy Learning**
  Lin, K., Ragunath, V., McAlinden, A., Prasad, A., Wu, J., Zhu, Y., Bohg, J.
  edited by Lim, J., Song, S., Park, H. W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2025: 3631-3646

- **MOTION TRACKS: A Unified Representation for Human-Robot Transfer in Few-Shot Imitation Learning**
  Ren, J., Sundaresan, P., Sadigh, D., Choudhury, S., Bohg, J.
  edited by Ott, C.
  IEEE.2025: 8802-8810

- **Points2Plans: From Point Clouds to Long-Horizon Plans with Composable Relational Dynamics**
  Huang, Y., Agia, C., Wu, J., Hermans, T., Bohg, J.
  edited by Ott, C.
  IEEE.2025: 1208-1216

- **Causal-PIK: Causality-based Physical Reasoning with a Physics-Informed Kernel**
  Pares-Morlans, C., Yi, M., Chen, C., Wu, S. A., Antonova, R., Gerstenberg, T., Bohg, J.
  edited by Singh, A., Fazel, M., Hsu, D., Lacoste-Julien, S., Berkenkamp, F., Maharaj, T., Wagstaff, K., Zhu, J.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2025: 44874-44886

- **Development and Evaluation of a Learning-Based Model for Real-Time Haptic Texture Rendering** *IEEE TRANSACTIONS ON HAPTICS*
  Heravi, N., Culbertson, H., Okamura, A. M., Bohg, J.
  2024; 17 (4): 705-716

- **ShaSTA: Modeling Shape and Spatio-Temporal Affinities for 3D Multi-Object Tracking** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Sadjadpour, T., Li, J., Ambrus, R., Bohg, J.
  2024; 9 (5): 4273-4280

- **EquivAct: SIM(3)-Equivariant Visuomotor Policies beyond Rigid Object Manipulation**
  Yang, J., Deng, C., Wu, J., Antonoval, R., Guibasl, L., Bohg, J., IEEE

IEEE.2024: 9249-9255

- **Get a Grip: Multi-Finger Grasp Evaluation at Scale Enables Robust Sim-to-Real Transfer**
  Lum, T., Li, A. H., Culbertson, P., Srinivasan, K., Ames, A. D., Schwager, M., Bohg, J.
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **AO-Grasp: Articulated Object Grasp Generation**
  Morlans, C., Chen, C., Weng, Y., Yi, M., Huang, Y., Heppert, N., Zhou, L., Guibas, L., Bohg, J., IEEE
  IEEE.2024: 13096-13103

- **Unpacking Failure Modes of Generative Policies: Runtime Monitoring of Consistency and Progress**
  Agia, C., Sinha, R., Yang, J., Cao, Z., Antonova, R., Pavone, M., Bohg, J.
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **Neural Attention Field: Emerging Point Relevance in 3D Scenes for One-Shot Dexterous Grasping**
  Wang, Q., Deng, C., Lum, T., Chen, Y., Yang, Y., Bohg, J., Zhu, Y., Guibas, L.
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **RT-Sketch: Goal-Conditioned Imitation Learning from Hand-Drawn Sketches**
  Sundaresan, P., Vuong, Q., Gu, J., Xu, P., Xiao, T., Kirmani, S., Yu, T., Stark, M., Jain, A., Hausman, K., Sadigh, D., Bohg, J., Schaal, et al
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **APRICOT: Active Preference Learning and Constraint-Aware Task Planning with LLMs**
  Wang, H., Chin, N., Gonzalez-Pumariega, G., Sun, X., Sunkara, N., Pace, M., Bohg, J., Choudhury, S.
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **TidyBot plus plus : An Open-Source Holonomic Mobile Manipulator for Robot Learning**
  Wu, J., Chong, W., Holmberg, R., Prasad, A., Gao, Y., Khatib, O., Song, S., Rusinkiewicz, S., Bohg, J.
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **SHADOW: Leveraging Segmentation Masks for Cross-Embodiment Policy Transfer**
  Lepert, M., Doshi, R., Bohg, J.
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **EquiBot: SIM(3)-Equivariant Diffusion Policy for Generalizable and Data Efficient Learning**
  Yang, J., Cao, Z., Deng, C., Antonova, R., Song, S., Bohg, J.
  edited by Kroemer, O., Agrawal, P., Burgard, W.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2024

- **Robot Fine-Tuning Made Easy: Pre-Training Rewards and Policies for Autonomous Real-World Reinforcement Learning**
  Yang, J., Mark, M., Vu, B., Sharma, A., Bohg, J., Finn, C., IEEE
  IEEE.2024: 4804-4811

- **Tactile-Informed Action Primitives Mitigate Jamming in Dense Clutter**
  Brouwer, D., Citron, J., Choi, H., Lepert, M., Lin, M., Bohg, J., Cutkosky, M., IEEE
  IEEE.2024: 7991-7997

- **Open X-Embodiment: Robotic Learning Datasets and RT-X Models**
  O'Neill, A., Rehman, A., Gupta, A., Maddukuri, A., Gupta, A., Padalkar, A., Lee, A., Pooley, A., Gupta, A., Mandlekar, A., Jain, A., Tung, A., Bewley, et al
  IEEE.2024: 6892-6903

- **COAST: COnstraints And STreams for Task and Motion Planning**
  Vu, B., Migimatsu, M., Bohg, J., IEEE
  IEEE.2024: 14875-14881
- **Design and Control of Roller Grasper V3 for In-Hand Manipulation** *IEEE TRANSACTIONS ON ROBOTICS*
  Yuan, S., Shao, L., Feng, Y., Sun, J., Xue, T., Yako, C. L., Bohg, J., Salisbury, J.
  2024; 40: 4222-4234
- **Text2Motion: from natural language instructions to feasible plans** *AUTONOMOUS ROBOTS*
  Lin, K., Agia, C., Migimatsu, T., Pavone, M., Bohg, J.
  2023; 47 (8): 1345-1365
- **TidyBot: personalized robot assistance with large language models** *AUTONOMOUS ROBOTS*
  Wu, J., Antonova, R., Kan, A., Lepert, M., Zeng, A., Song, S., Bohg, J., Rusinkiewicz, S., Funkhouser, T.
  2023
- **Deep Learning Approaches to Grasp Synthesis: A Review** *IEEE TRANSACTIONS ON ROBOTICS*
  Newbury, R., Gu, M., Chumbley, L., Mousavian, A., Eppner, C., Leitner, J., Bohg, J., Morales, A., Asfour, T., Kragic, D., Fox, D., Cosgun, A.
  2023
- **The OBJECTFOLDER BENCHMARK: Multisensory Learning with Neural and Real Objects**
  Gao, R., Dou, Y., Li, H., Agarwal, T., Bohg, J., Li, Y., Fei-Fei, L., Wu, J., IEEE
  IEEE COMPUTER SOC.2023: 17276-17286
- **KITE: Keypoint-Conditioned Policies for Semantic Manipulation**
  Sundaresan, P., Belkhale, S., Sadigh, D., Bohg, J.
  edited by Tan, J., Toussaint, M., Darvish, K.
  JMLR-JOURNAL MACHINE LEARNING RESEARCH.2023
- **In-Hand Manipulation of Unknown Objects with Tactile Sensing for Insertion**
  Pan, C., Lepert, M., Yuan, S., Antonova, R., Bohg, J., IEEE
  IEEE.2023: 8765-8771
- **CARTO: Category and Joint Agnostic Reconstruction of ARTiculated Objects**
  Heppert, N., Irshad, M., Zakharov, S., Liu, K., Ambrus, R., Bohg, J., Valada, A., Kollar, T., IEEE
  IEEE COMPUTER SOC.2023: 21201-21210
- **STAP: Sequencing Task-Agnostic Policies**
  Agia, C., Migimatsu, T., Wu, J., Bohg, J., IEEE
  IEEE.2023: 7951-7958
- **Visuomotor Control in Multi-Object Scenes Using Object-Aware Representations**
  Heravi, N., Wahid, A., Lynch, C., Florence, P., Armstrong, T., Tompson, J., Sermanet, P., Bohg, J., Dwibedi, D., IEEE
  IEEE.2023: 9515-9522
- **TidyBot: Personalized Robot Assistance with Large Language Models**
  Wu, J., Antonova, R., Kan, A., Lepert, M., Zeng, A., Song, S., Bohg, J., Rusinkiewicz, S., Funkhouser, T., IEEE
  IEEE.2023: 3546-3553
- **Active Task Randomization: Learning Robust Skills via Unsupervised Generation of Diverse and Feasible Tasks**
  Fang, K., Migimatsu, T., Mandlekar, A., Fei-Fei, L., Bohg, J., IEEE
  IEEE.2023: 1924-1931
- **Learning Tool Morphology for Contact-Rich Manipulation Tasks with Differentiable Simulation**
  Li, M., Antonova, R., Sadigh, D., Bohg, J., IEEE
  IEEE.2023: 1859-1865
- **A Bayesian Treatment of Real-to-Sim for Deformable Object Manipulation** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Antonova, R., Yang, J., Sundaresan, P., Fox, D., Ramos, F., Bohg, J.
  2022; 7 (3): 5819-5826

- **Predicting Hand-Object Interaction for Improved Haptic Feedback in Mixed Reality** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Salvato, M., Heravi, N., Okamura, A. M., Bohg, J.
  2022; 7 (2): 3851-3857
- **Vision-Only Robot Navigation in a Neural Radiance World** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Adamkiewicz, M., Chen, T., Caccavale, A., Gardner, R., Culbertson, P., Bohg, J., Schwager, M.
  2022; 7 (2): 4606-4613
- **Symbolic State Estimation with Predicates for Contact-Rich Manipulation Tasks**
  Migimatsu, T., Lian, W., Bohg, J., Schaal, S., IEEE
  IEEE.2022: 1702-1709
- **OBJECTFOLDER 2.0: A Multisensory Object Dataset for Sim2Real Transfer**
  Gao, R., Si, Z., Chang, Y., Clarke, S., Bohg, J., Li Fei-Fei, Yuan, W., Wu, J., IEEE COMP SOC
  IEEE COMPUTER SOC.2022: 10588-10598
- **DiffCloud: Real-to-Sim from Point Clouds with Differentiable Simulation and Rendering of Deformable Objects**
  Sundaresan, P., Antonova, R., Bohg, J., IEEE
  IEEE.2022: 10828-10835
- **Whisker-Inspired Tactile Sensing for Contact Localization on Robot Manipulators**
  Lin, M. A., Reyes, E., Bohg, J., Cutkosky, M. R., IEEE
  IEEE.2022: 7817-7824
- **Category-Independent Articulated Object Tracking with Factor Graphs**
  Heppert, N., Migimatsu, T., Yi, B., Chen, C., Bohg, J., IEEE
  IEEE.2022: 3800-3807
- **Grounding Predicates through Actions open(drawer) open(drawer)**
  Migimatsu, T., Bohg, J., IEEE
  IEEE.2022: 3498-3504
- **Dynamic multi-robot task allocation under uncertainty and temporal constraints** *AUTONOMOUS ROBOTS*
  Choudhury, S., Gupta, J. K., Kochenderfer, M. J., Sadigh, D., Bohg, J.
  2021
- **Concept2Robot: Learning manipulation concepts from instructions and human demonstrations** *INTERNATIONAL JOURNAL OF ROBOTICS RESEARCH*
  Shao, L., Migimatsu, T., Zhang, Q., Yang, K., Bohg, J.
  2021
- **Learning latent actions to control assistive robots** *AUTONOMOUS ROBOTS*
  Losey, D. P., Jeon, H., Li, M., Srinivasan, K., Mandlekar, A., Garg, A., Bohg, J., Sadigh, D.
  2021: 1-33
- **How to train your differentiable filter** *AUTONOMOUS ROBOTS*
  Kloss, A., Martius, G., Bohg, J.
  2021
- **Detect, Reject, Correct: Crossmodal Compensation of Corrupted Sensors**
  Lee, M. A., Tan, M., Zhu, Y., Bohg, J., IEEE
  IEEE.2021: 909-916
- **Differentiable Factor Graph Optimization for Learning Smoothers**
  Yi, B., Lee, M. A., Kloss, A., Martin-Martin, R., Bohg, J., IEEE
  IEEE.2021: 1339-1345
- **TrajectoTree: Trajectory Optimization Meets Tree Search for Planning Multi-contact Dexterous Manipulation** *2021 IEEE/RSJ International Conference on Intelligent Robots and Systems (IROS)*
  Chen, C., Culbertson, P., Lepert, M., Schwager, M., Bohg, J.

IEEE.2021: 8262-8268

- **Probabilistic 3D Multi-Modal, Multi-Object Tracking for Autonomous Driving**
  Chiu, H., Lie, J., Ambrus, R., Bohg, J., IEEE
  IEEE.2021: 14227-14233
- **Interpreting Contact Interactions to Overcome Failure in Robot Assembly Tasks**
  Zachares, P. A., Lee, M. A., Lian, W., Bohg, J., IEEE
  IEEE.2021: 3410-3417
- **OmniHang: Learning to Hang Arbitrary Objects using Contact Point Correspondences and Neural Collision Estimation**
  You, Y., Shao, L., Migimatsu, T., Bohg, J., IEEE
  IEEE.2021: 5921-5927
- **Combining learned and analytical models for predicting action effects from sensory data** *INTERNATIONAL JOURNAL OF ROBOTICS RESEARCH*
  Kloss, A., Schaal, S., Bohg, J.
  2020
- **Making Sense of Vision and Touch: Learning Multimodal Representations for Contact-Rich Tasks** *IEEE TRANSACTIONS ON ROBOTICS*
  Lee, M. A., Zhu, Y., Zachares, P., Tan, M., Srinivasan, K., Savarese, S., Fei-Fei, L., Garg, A., Bohg, J.
  2020; 36 (3): 582–96
- **Learning Task-Oriented Grasping From Human Activity Datasets** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Kokic, M., Kragic, D., Bohg, J.
  2020; 5 (2): 3352–59
- **Self-Supervised Learning of State Estimation for Manipulating Deformable Linear Objects** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Yan, M., Zhu, Y., Jin, N., Bohg, J.
  2020; 5 (2): 2372–79
- **Object-Centric Task and Motion Planning in Dynamic Environments** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Migimatsu, T., Bohg, J.
  2020; 5 (2): 844–51
- **UniGrasp: Learning a Unified Model to Grasp With Multifingered Robotic Hands** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Shao, L., Ferreira, F., Jorda, M., Nambiar, V., Luo, J., Solowjow, E., Ojea, J., Khatib, O., Bohg, J.
  2020; 5 (2): 2286–93
- **Concept2Robot: Learning Manipulation Concepts from Instructions and Human Demonstrations**
  Shao, L., Migimatsu, T., Zhang, Q., Yang, K., Bohg, J.
  edited by Toussaint, M., Bicchi, A., Hermans, T.
  MIT PRESS.2020
- **Accurate Vision-based Manipulation through Contact Reasoning**
  Kloss, A., Bauza, M., Wu, J., Tenenbaum, J. B., Rodriguez, A., Bohg, J., IEEE
  IEEE.2020: 6738-6744
- **Learning Hierarchical Control for Robust In-Hand Manipulation**
  Li, T., Srinivasan, K., Meng, M., Yuan, W., Bohg, J., IEEE
  IEEE.2020: 8855-8862
- **Learning to Scaffold the Development of Robotic Manipulation Skills**
  Shao, L., Migimatsu, T., Bohg, J., IEEE
  IEEE.2020: 5671-5677
- **Learning User-Preferred Mappings for Intuitive Robot Control**
  Li, M., Losey, D. P., Bohg, J., Sadigh, D., IEEE
  IEEE.2020: 10960-10967

- **Learning Topological Motion Primitives for Knot Planning**
  Yan, M., Li, G., Zhu, Y., Bohg, J., IEEE
  IEEE.2020: 9457-9464
- **Multimodal Sensor Fusion with Differentiable Filters**
  Lee, M. A., Yi, B., Martin-Martin, R., Savarese, S., Bohg, J., IEEE
  IEEE.2020: 10444-10451
- **Dynamic Multi-Robot Task Allocation under Uncertainty and Temporal Constraints**
  Choudhury, S., Gupta, J. K., Kochendeefer, M. J., Sadigh, D., Bohg, J.
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  MIT PRESS.2020
- **Predicting grasp success in the real world - A study of quality metrics and human assessment** *ROBOTICS AND AUTONOMOUS SYSTEMS*
  Rubert, C., Kappler, D., Bohg, J., Morales, A.
  2019; 121
- **Variable Impedance Control in End-Effector Space: An Action Space for Reinforcement Learning in Contact-Rich Tasks**
  Martin-Martin, R., Lee, M. A., Gardner, R., Savarese, S., Bohg, J., Garg, A., IEEE
  IEEE.2019: 1010–17
- **MeteorNet: Deep Learning on Dynamic 3D Point Cloud Sequences**
  Liu, X., Yan, M., Bohg, J., IEEE
  IEEE.2019: 9245–54
- **Leveraging Contact Forces for Learning to Grasp**
  Merzic, H., Bogdanovic, M., Kappler, D., Righetti, L., Bohg, J., IEEE
  edited by Howard, A., Althoefer, K., Arai, F., Arrichiello, F., Caputo, B., Castellanos, J., Hauser, K., Isler, Kim, J., Liu, H., Oh, P., Santos, Scaramuzza, D., Ude, A., Voyles, R., Yamane, K., Okamura, A.
  IEEE.2019: 3615–21
- **Making Sense of Vision and Touch: Self-Supervised Learning of Multimodal Representations for Contact-Rich Tasks**
  Lee, M. A., Zhu, Y., Srinivasan, K., Shah, P., Savarese, S., Li Fei-Fei, Garg, A., Bohg, J., IEEE
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  IEEE.2019: 8943–50
- **Learning to Estimate Pose and Shape of Hand-Held Objects from RGB Images**
  Kokic, M., Kragic, D., Bohg, J., IEEE
  IEEE.2019: 3980–87
- **Motion-Based Object Segmentation Based on Dense RGB-D Scene Flow** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Shao, L., Shah, P., Dwaracherla, V., Bohg, J.
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- **Interactive Perception: Leveraging Action in Perception and Perception in Action** *IEEE TRANSACTIONS ON ROBOTICS*
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- **Reports on the 2017 AAAI Spring Symposium Series** *AI MAGAZINE*
  Bohg, J., Boix, X., Chang, N., Chu, V., Churchill, E. F., Fang, F., Feldman, J., Gonzalez, A. J., Kido, T., Lawless, W. F., Montana, J. L., Ontanon, S., Sinapov, et al
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- **Probabilistic Articulated Real-Time Tracking for Robot Manipulation** *IEEE ROBOTICS AND AUTOMATION LETTERS*
  Cifuentes, C., Issac, J., Wuethrich, M., Schaal, S., Bohg, J.
  2017; 2 (2): 577–84
- **On the relevance of grasp metrics for predicting grasp success**
  Rubert, C., Kappler, D., Morales, A., Schaal, S., Bohg, J.

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IEEE.2017: 265–72

- **Big Data on Robotics.** *Big data*
  Bohg, J., Ciocarlie, M., Civera, J., Kavraki, L. E.
  2016; 4 (4): 195-196

- **Automatic LQR Tuning Based on Gaussian Process Global Optimization**
  Marco, A., Hennig, P., Bohg, J., Schaal, S., Trimpe, S.
  edited by Okamura, A., Menciassi, A., Ude, A., Burschka, D., Lee, D., Arrichiello, F., Liu, H., Moon, H., Neira, J., Sycara, K., Yokoi, K., Martinet, P., Oh, P., Valdastri, P., Krovi
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