















- Brooks, A.; Makarenko, A.; and Upcroft, B. 2008. Gaussian process models for indoor and outdoor sensor-centric robot localization. *IEEE Trans. Robotics* 24(6):1341–1351.
- Cao, N.; Low, K. H.; and Dolan, J. M. 2013. Multi-robot informative path planning for active sensing of environmental phenomena: A tale of two algorithms. In *Proc. AAMAS*, 7–14.
- Chen, K., and Guestrin, C. 2007. <http://www.select.cs.cmu.edu/data/index.html>.
- Chen, J.; Low, K. H.; Tan, C. K.-Y.; Oran, A.; Jaillet, P.; Dolan, J. M.; and Sukhatme, G. S. 2012. Decentralized data fusion and active sensing with mobile sensors for modeling and predicting spatiotemporal traffic phenomena. In *Proc. UAI*, 163–173.
- Chen, J.; Cao, N.; Low, K. H.; Ouyang, R.; Tan, C. K.-Y.; and Jaillet, P. 2013. Parallel Gaussian process regression with low-rank covariance matrix approximations. In *Proc. UAI*, 152–161.
- Chen, J.; Low, K. H.; and Tan, C. K.-Y. 2013. Gaussian process-based decentralized data fusion and active sensing for mobility-on-demand system. In *Proc. RSS*.
- Csató, L., and Opper, M. 2002. Sparse online Gaussian processes. *Neural Computation* 14(2):641–669.
- Dolan, J. M.; Podnar, G.; Stancliff, S.; Low, K. H.; Elfes, A.; Higinbotham, J.; Hosler, J. C.; Moisan, T. A.; and Moisan, J. 2009. Cooperative aquatic sensing using the telesupervised adaptive ocean sensor fleet. In *Proc. SPIE Conference on Remote Sensing of the Ocean, Sea Ice, and Large Water Regions*, volume 7473.
- Ferris, B.; Fox, D.; and Lawrence, N. 2007. WiFi-SLAM using Gaussian process latent variable models. In *Proc. IJCAI*, 2480–2485.
- Ferris, B.; Hähnel, D.; and Fox, D. 2006. Gaussian processes for signal strength-based location estimation. In *Proc. RSS*.
- Gerkey, B. P.; Vaughan, R. T.; and Howard, A. 2003. The Player/Stage project: Tools for multi-robot and distributed sensor systems. In *Proc. ICAR*, 317–323.
- Hoang, T. N.; Low, K. H.; Jaillet, P.; and Kankanhalli, M. 2014. Nonmyopic  $\epsilon$ -Bayes-optimal active learning of Gaussian processes. In *Proc. ICML*.
- Ko, J., and Fox, D. 2009a. GP-BayesFilters: Bayesian filtering using Gaussian process prediction and observation models. *Autonomous Robots* 27(1):75–90.
- Ko, J., and Fox, D. 2009b. Learning GP-BayesFilters via Gaussian process latent variable models. In *Proc. RSS*.
- Krause, A.; Singh, A.; and Guestrin, C. 2008. Near-optimal sensor placements in Gaussian processes: Theory, efficient algorithms and empirical studies. *JMLR* 9:235–284.
- Low, K. H.; Gordon, G. J.; Dolan, J. M.; and Khosla, P. 2007. Adaptive sampling for multi-robot wide-area exploration. In *Proc. IEEE ICRA*, 755–760.
- Low, K. H.; Chen, J.; Dolan, J. M.; Chien, S.; and Thompson, D. R. 2012. Decentralized active robotic exploration and mapping for probabilistic field classification in environmental sensing. In *Proc. AAMAS*, 105–112.
- Low, K. H.; Dolan, J. M.; and Khosla, P. 2008. Adaptive multi-robot wide-area exploration and mapping. In *Proc. AAMAS*, 23–30.
- Low, K. H.; Dolan, J. M.; and Khosla, P. 2009. Information-theoretic approach to efficient adaptive path planning for mobile robotic environmental sensing. In *Proc. ICAPS*, 233–240.
- Low, K. H.; Dolan, J. M.; and Khosla, P. 2011. Active Markov information-theoretic path planning for robotic environmental sensing. In *Proc. AAMAS*, 753–760.
- Low, K. H.; Leow, W. K.; and Ang, Jr., M. H. 2002a. A hybrid mobile robot architecture with integrated planning and control. In *Proc. AAMAS*, 219–226.
- Low, K. H.; Leow, W. K.; and Ang, Jr., M. H. 2002b. Integrated planning and control of mobile robot with self-organizing neural network. In *Proc. IEEE ICRA*, 3870–3875.
- Low, K. H.; Leow, W. K.; and Ang, Jr., M. H. 2005. An ensemble of cooperative extended Kohonen maps for complex robot motion tasks. *Neural Comput.* 17(6):1411–1445.
- Natarajan, P.; Hoang, T. N.; Low, K. H.; and Kankanhalli, M. 2012a. Decision-theoretic approach to maximizing observation of multiple targets in multi-camera surveillance. In *Proc. AAMAS*, 155–162.
- Natarajan, P.; Hoang, T. N.; Low, K. H.; and Kankanhalli, M. 2012b. Decision-theoretic coordination and control for active multi-camera surveillance in uncertain, partially observable environments. In *Proc. ICDSC*.
- Natarajan, P.; Low, K. H.; and Kankanhalli, M. 2014. Decision-theoretic approach to maximizing fairness in multi-target observation in multi-camera surveillance. In *Proc. AAMAS*.
- Ouyang, R.; Low, K. H.; Chen, J.; and Jaillet, P. 2014. Multi-robot active sensing of non-stationary Gaussian process-based environmental phenomena. In *Proc. AAMAS*.
- Podnar, G.; Dolan, J. M.; Low, K. H.; and Elfes, A. 2010. Telesupervised remote surface water quality sensing. In *Proc. IEEE Aerospace Conference*.
- Quiñonero-Candela, J., and Rasmussen, C. E. 2005. A unifying view of sparse approximate Gaussian process regression. *JMLR* 6:1939–1959.
- Rasmussen, C. E., and Williams, C. K. I. 2006. *Gaussian Processes for Machine Learning*. Cambridge, MA: MIT Press.
- Snelson, E. L. 2007. *Flexible and efficient Gaussian process models for machine learning*. Ph.D. Thesis, University College London, London, UK.
- Thrun, S.; Burgard, W.; and Fox, D. 2005. *Probabilistic Robotics*. Cambridge, MA: MIT Press.
- Xu, N.; Low, K. H.; Chen, J.; Lim, K. K.; and Özgül, E. B. 2014. GP-Localize: Persistent mobile robot localization using online sparse Gaussian process observation model. arXiv:1404.5165.
- Yu, J.; Low, K. H.; Oran, A.; and Jaillet, P. 2012. Hierarchical Bayesian nonparametric approach to modeling and learning the wisdom of crowds of urban traffic route planning agents. In *Proc. IAT*, 478–485.