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This book includes the proceedings of the 12th RoboCup International Symposium, held in Suzhou, China, on July 15-18, 2008 in conjunction with Soccer, Rescue, @Home and Junior competitions and demonstrations.

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In the RoboCup domain, many robot systems use low-cost image sensors to perceive the robot's environment and to locate the robot in its environment. The image processing typically has to handle image distortions such as motion blur, noise, and the properties

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The 12th annual RoboCup International Symposium was held during July 15-18, 2008 in conjunction with RoboCup 2008 Competitions and Demonstrations. The symposium represents the core meeting for the presentation and discussion of sci- tific contributions in diverse areas related to the main threads within RoboCupSoccer,

[RoboCupRescue, RoboCup](#)

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RoboCup 2008: Robot Soccer World Cup XII, pp. 189-199 inproceedings DOI URL. Abstract: This paper introduces a method for multi-robot localization which can be applied to more than two robots without identifying each of them individually. The Monte Carlo localization for the single robot case is extended using negative landmark information and shared belief state in addition to perception. A

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The name RoboCup is a contraction of the competition's full name, "Robot Soccer World Cup", but there are many other stages of the competition such as "RoboCupRescue", "RoboCup@Home" and "RoboCupJunior".

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RoboCup is an international scientific initiative with the goal to advance the state of the art of intelligent robots. When established in 1997, the original mission was to field a team of robots capable of winning against the human soccer World Cup champions by 2050.