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DEPARTMENT OF ELECTRICAL, ELECTRONIC  
AND COMPUTER ENGINEERING

EAI 320 - INTELLIGENT SYSTEMS

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## LaTeX template

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sXXXXXXXX

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# DECLARATION OF ORIGINALITY

## UNIVERSITY OF PRETORIA

The University of Pretoria places great emphasis upon integrity and ethical conduct in the preparation of all written work submitted for academic evaluation.

While academic staff teach you about referencing techniques and how to avoid plagiarism, you too have a responsibility in this regard. If you are at any stage uncertain as to what is required, you should speak to your lecturer before any written work is submitted.

You are guilty of plagiarism if you copy something from another author's work (e.g. a book, an article or a website) without acknowledging the source and pass it off as your own. In effect you are stealing something that belongs to someone else. This is not only the case when you copy work word-for-word (verbatim), but also when you submit someone else's work in a slightly altered form (paraphrase) or use a line of argument without acknowledging it. You are not allowed to use work previously produced by another student. You are also not allowed to let anybody copy your work with the intention of passing it off as his/her work.

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Full names of student: \_\_\_\_\_

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Topic of work: \_\_\_\_\_

### Declaration

1. I understand what plagiarism is and am aware of the University's policy in this regard.
2. I declare that this assignment report is my own original work. Where other people's work has been used (either from a printed source, Internet or any other source), this has been properly acknowledged and referenced in accordance with departmental requirements.
3. I have not used work previously produced by another student or any other person to hand in as my own.
4. I have not allowed, and will not allow, anyone to copy my work with the intention of passing it off as his or her own work.

SIGNATURE: \_\_\_\_\_ DATE: \_\_\_\_\_

# 1 Introduction

This is a reference [1]

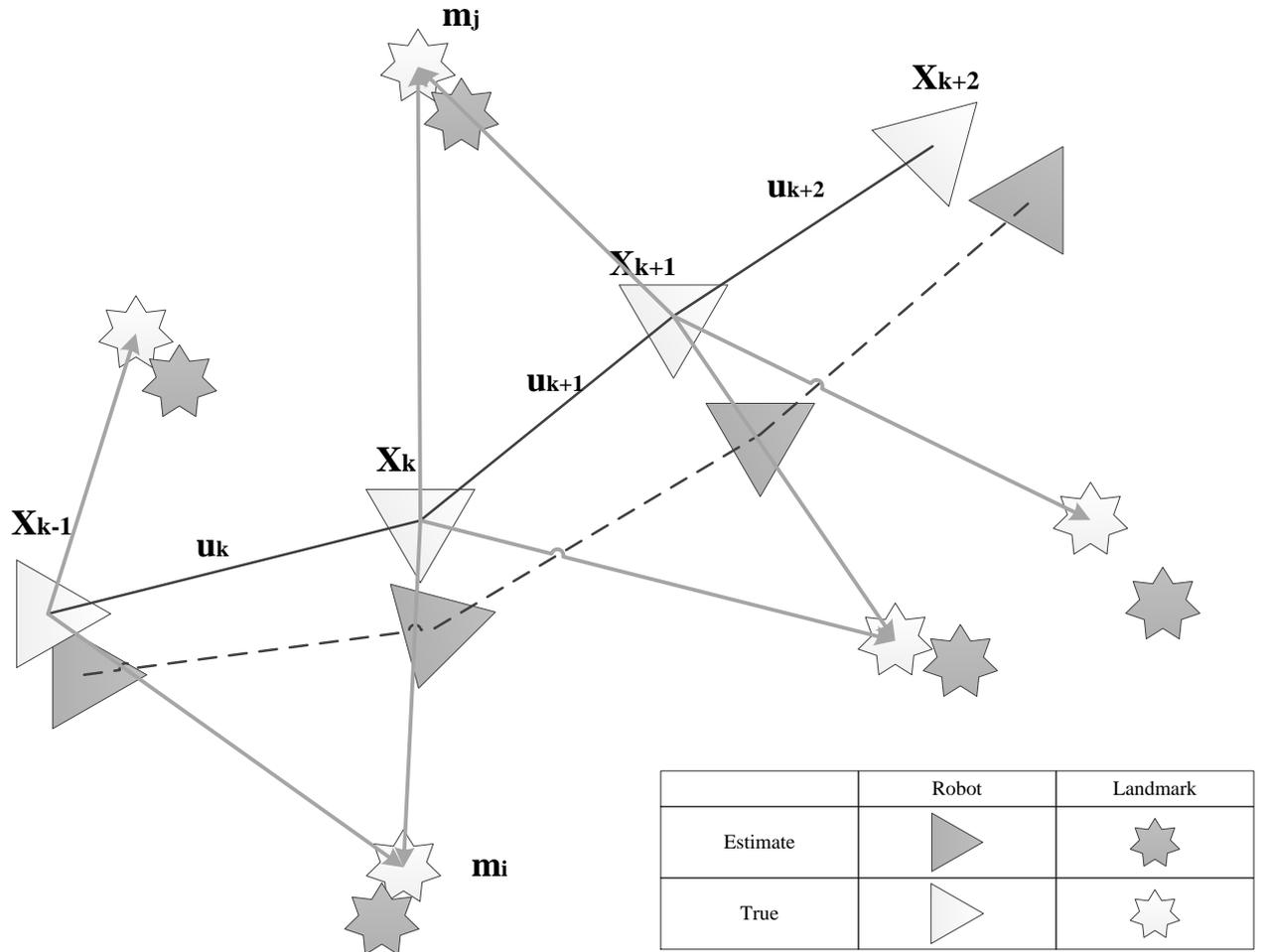


Figure 1.1: This is a figure.

$$P(\mathbf{x}_k, \mathbf{m} | \mathbf{Z}_{0:k}, \mathbf{U}_{0:k}, \mathbf{x}_0) = \frac{P(\mathbf{z}_k | \mathbf{x}_k, \mathbf{m}) P(\mathbf{x}_k, \mathbf{m} | \mathbf{Z}_{0:k-1}, \mathbf{U}_{0:k}, \mathbf{x}_0)}{P(\mathbf{z}_k | \mathbf{Z}_{0:k-1}, \mathbf{U}_{0:k})}. \quad (1.1)$$

2 ...

# Bibliography

- [1] S. Blackmand and R. Popoli, *Design and Analysis of Modern Tracking Systems*. Artech House, first ed., 1999.